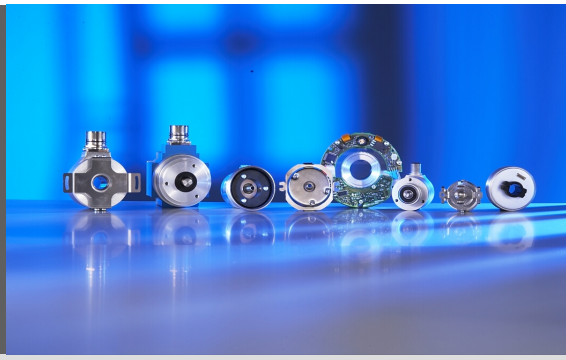
HIPERFACE DSL



HIPERFACE DSL INTERFACE

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HIPERFACE® DSL

SICK

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This documentation applies to the HIPERFACE DSL®, release version 1.05, release date May 31, 2013.

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Table of contents

1. Scope of application of the document ... 3
1.1. Symbols used ... 3
1.2. HIPERFACE DSL® for Motor Feedback ... 4
1.3. Features of HIPERFACE DSL® ... 5
1.4. Associated documents ... 6

2. Protocol overview ... 7
2.1. Process data channel ... 10
2.2. Safe Channel ... 10
2.3. Safe Channel 2 ... 11
2.4. Parameters Channel ... 11
2.5. SensorHub Channel ... 12

3. Hardware installation ... 13
3.1. Interface circuit ... 13
3.2. FPGA IP Core ... 16
3.3. Cable specification ... 23

4. Interfaces ... 25
4.1. Interface 1 ... 26
4.2. Interface 2 ... 26
4.3. SPI PIPE Interface ... 27
4.4. Control signals ... 29
4.5. Reset ... 31
4.6. Test signals ... 31

5. Register diagram ... 34
5.1. Explanation of the registers ... 35
5.2. Online Status ... 36
5.3. DSL Master function register on Channel 1 ... 40
5.4. DSL Master function register on Channel 2 ... 71
5.5. Function register for the DSL Slave ... 77

6. Central functions ... 81
6.1. System start ... 81
6.2. System diagnostics ... 82
6.3. Fast position ... 84
6.4. Safe position, Channel 1 ... 87
6.5. Safe position, Channel 2 ... 88
6.6. Parameters Channel ... 90
6.7. Status and error messages ... 99

7. Motor feedback system resources ... 108
7.1. Access to resources ... 108
7.2. Resources list ... 111

Keywords index ... 165

Glossary ... 166

Versions ... 167

1. Scope of application of the document

1.1. Symbols used

Note/tip
Notes refer to special features of the device. Please pay attention to these notes. They often contain important information.
Tips provide additional information that facilitates using the documentation.

Safety notes
Safety notes contain information about specific or potential dangers, and misuse of the application. This information is to prevent injury.
Read and follow the safety notes carefully.

1.2. HIPERFACE DSL® for Motor Feedback

This document describes the use and implementation of the HIPERFACE DSL® data protocol installed in motor feedback systems of servo drives.

HIPERFACE DSL® is a purely digital protocol that requires a minimum of connection cables between frequency inverter and motor feedback system. The robustness of the protocol enables the connection to the motor feedback system via the motor connection cable.

Motor feedback systems with the HIPERFACE DSL® interface can be used across all performance ranges and substantially simplify the installation of an encoder system in the drive:

- Standardized digital interface (RS485)
- Analog components for the encoder interface are not required
- Standardized interface between the frequency inverter application and the protocol logic

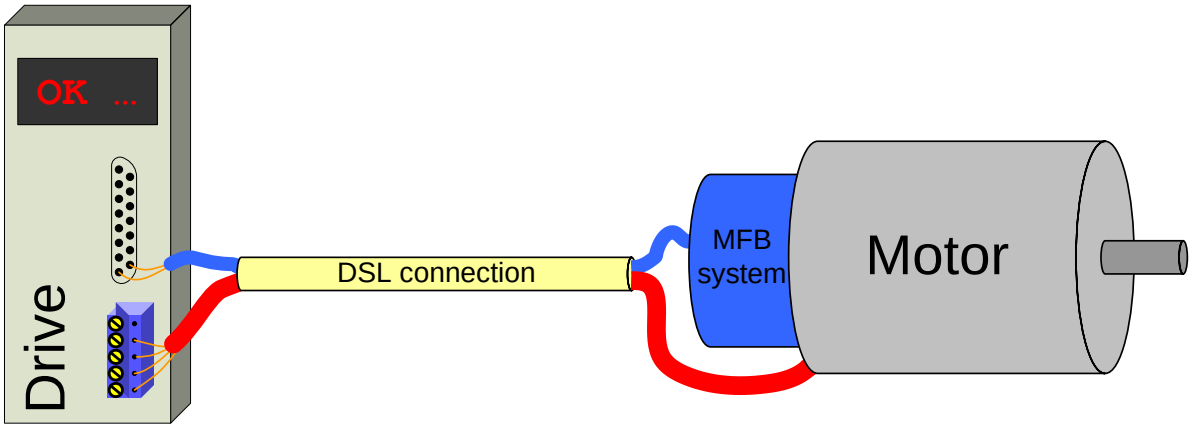


Figure 1: Drive system with HIPERFACE DSL®

Based on the name for the predecessor protocol, the SICK HIPERFACE®, the name HIPERFACE DSL® stands for HIgh PERformance InterFACE Digital Servo Link.

This interface takes into account all the current requirements of digital motor feedback systems and also contains future enhancements for the manufacturers of frequency inverters.

1.3. Features of HIPERFACE DSL®

Some of the main advantages of HIPERFACE DSL® are based on the opportunity for connection of the encoder:

- A digital interface on the frequency inverter for all communication with the motor feedback system. The interface complies with the RS485 standard with a transfer rate of 9.375 MBaud.
- Communication with the encoder via a dual cable
- Power supply and communication with the encoder can be carried out using the same dual cable. This is possible by the enhancement of the frequency - inverter with a transformer.
- The connection cables to the encoder can be routed as a shielded, twisted-pair cable in the power supply cable to the motor. This means that no encoder plug connector to the motor and to the frequency inverter is necessary.
- The cable length between the frequency inverter and the motor feedback system can be up to 100 m, without degradation of the operating performance.

The digital HIPERFACE DSL® protocol can be used for a variety of frequency inverter applications:

- For the feedback cycle of the frequency inverter's synchronous cyclic data that enables synchronous processing of position and rotation speed of the encoder.
- Shortest possible cycle time: 12.1 µs.
- Transmission of the safe position of the motor feedback system with a maximum cycle time of 192 µs.
- Redundant transmission of the safe position of the motor feedback system with a maximum cycle time of 192 µs, so that suitable motor feedback systems can be used in SIL2 applications (in accordance with IEC 61508).
- Transmission of the safe position of the motor feedback system on a second channel with a maximum cycle time of 192 µs, so that suitable motor feedback systems can be used in SIL3 applications (in accordance with IEC 61508).
- Parameter data channel for bi-directional general data transfer with a band width of up to 340 kBaud. This data includes an electronic type label for designation of the motor feedback system and for storage of frequency inverter data in the motor feedback system.
- SensorHub channel via which motor data from external sensors is transmitted, that are connected by the HIPERFACE DSL® SensorHub protocol to the motor feedback system.

The protocol is integrated into the frequency inverter in the form of hardware logic. This logic circuit is supplied by several manufacturers as an IP Core for FPGA components (FPGA = Field Programmable Gate Array).

- The available protocol logic enables free routing when installing the HIPERFACE DSL® IP Core. The protocol circuit can be installed along with the frequency inverter application on the same FPGA.
- Choice between full-duplex SPI interface (SPI = serial peripheral interface) or parallel interface between protocol logic and frequency inverter applications for standardized access to process data (position, rotation speed) and parameters.
- Fast additional full-duplex SPI interface between protocol logic and frequency inverter applications for standardized access to secondary position data
- Additional configurable SPI interfaces for output of the data from external sensors.
- Configurable interrupt output

1.4. Associated documents

Along with this manual, the following documents are relevant for the use of the HIPERFACE DSL® interface:

Document number	Title	Status
8 013 664	HIPERFACE DSL® safety manual	8/24/2012
8 013 737	DSL Master IP Core user manual	5/31/2013

Table 1: Associated documents

Individual encoder types with the HIPERFACE DSL® interface are described with the following documents:

- Data sheet
- Operating instructions
- Errata document

2. Protocol overview

HIPERFACE DSL® is a fast digital protocol for motor feedback systems for the connection between servo drive and motor feedback system. The protocol is installed in the transport layer in the frequency inverter using a digital logic circuit (DSL Master IP Core).

The position data are generated in two different ways in HIPERFACE DSL®, either in free running mode, in which the position values are sampled and transmitted as quickly as possible, or in SYNC mode, in which the position data are sampled and transmitted synchronously with a defined clock signal. With a frequency inverter application, this clock signal is normally the clock feedback of the frequency inverter.

In SYNC mode the protocol matches the time points for the sampling of the data without time fluctuations with the clock coming from the frequency inverter.

For each frequency inverter cycle at least one position value is sampled and transmitted with constant latency to the DSL Master. As the protocol matches the internal data transfer speed to the frequency inverter cycle, the overall transfer rate of the HIPERFACE DSL® depends on the frequency inverter clock.

The protocol package is matched to the various lengths, see Figure 2. Provided the frequency inverter cycle is long enough, additional sampling points can be positioned in the frequency inverter cycle, known as "extra" packages. The number of additional packages is programmed by the user with a distribution value.

The number of packages transmitted per frequency inverter cycle cannot be selected at random, as the lower and upper range length of a protocol package must be adhered to. This must be taken into account when setting the distribution value.

In free running mode, the frequency inverter cycle is not taken into account for sampling and transmission and the protocol uses the minimum package length.

It must be noted that the minimum package length in free running mode is shorter than the minimum package length in SYNC mode.

Table 2 shows the dependency of the lengths of the protocol packages using examples for the length of the frequency inverter cycle.

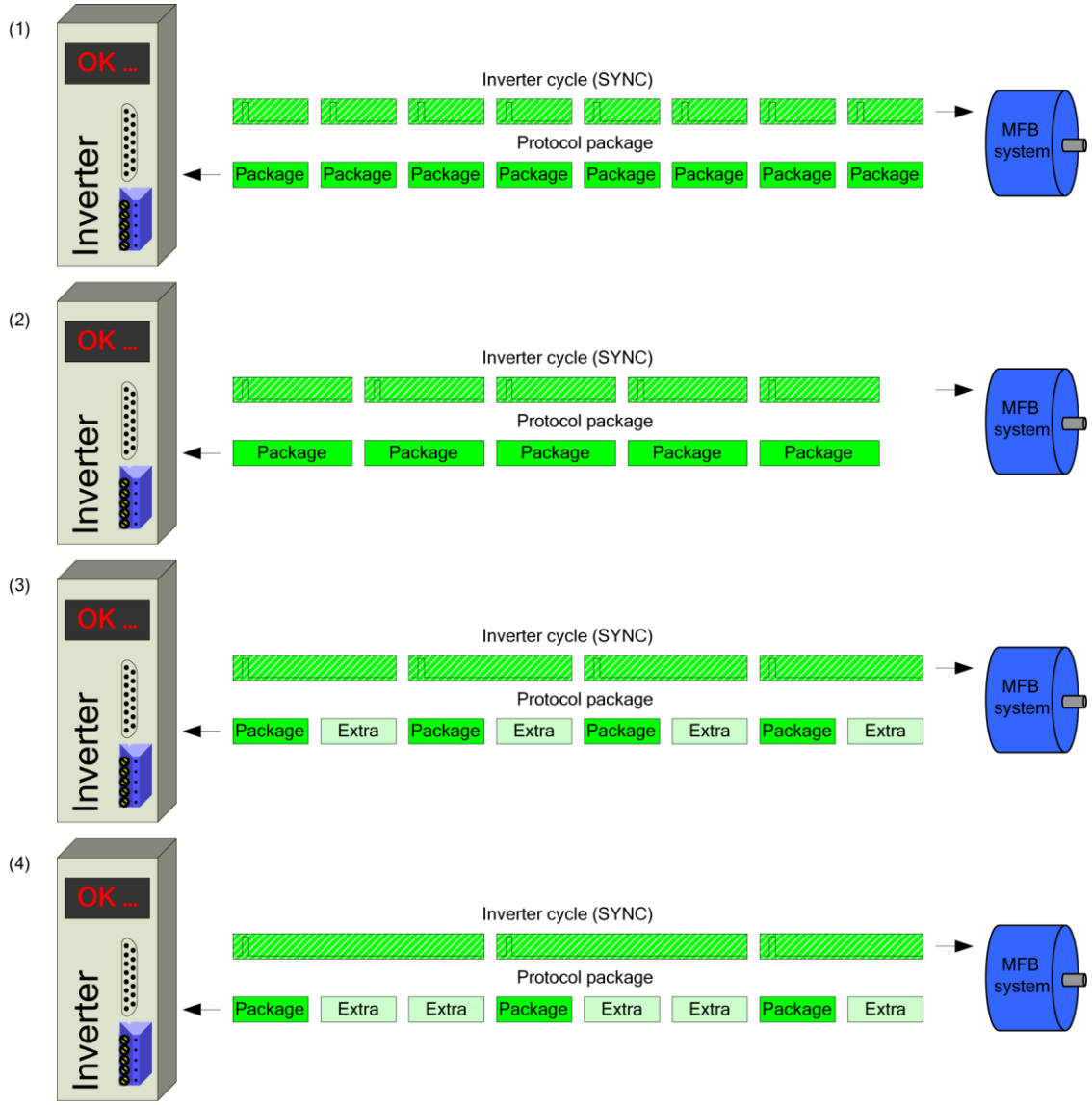


Figure 2: Length of protocol packages

Inverter cycle frequency (kHz)	Length of the frequency inverter cycle (µs)	Length of the protocol package (µs)	Protocol packages per frequency inverter cycle
2	500	12.50	40
4	250	12.50	20
6.25	160	13.33	12
8	125	12.50	10
16	62.5	12.50	5
40	25	12.50	2
41 to 84	23.8 to 12.1	23.8 to 12.1	1
Free running	--	11.52	--

Table 2: Frequency inverter cycle and length of protocol packages

In HIPERFACE DSL®, the data are transmitted over several channels. Each individual channel is adapted to different requirements according to its content. The cycle time of each individual channel varies with the length of the basic protocol package.

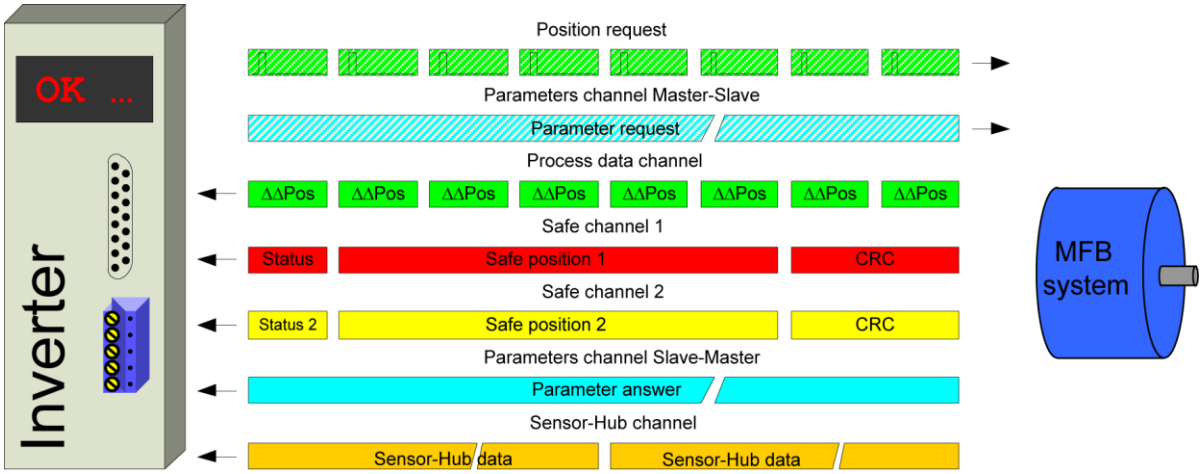


Figure 3: Data channels in HIPERFACE DSL®

Table 3 gives an overview of the characteristics of the various channels.

It should be noted that the minimum cycle time and the maximum band width only apply if the maximum number of sample points per frequency inverter cycle was programmed (refer to "Register synchronization control", section 5.3.2).

Channel in HIPERFACE DSL®	Function	Cycle time (µs)	Band width (kBaud)
Process data channel	Fast position, rotation speed	12.1 to 23.9	1321 to 669
Safe Channel	Safe position, status of Channel 1	96.8 to 191.2	660 to 334
Safe Channel 2	Safe position, status of Channel 2	96.8 to 191.2	660 to 334
Parameter channel	General data, parameters	Variable	330 to 167
SensorHub channel	External data	12.1 to 23.9	660 to 334

Table 3: Channels for protocol data

2.1. Process data channel

The position value of the motor feedback system is transferred on the process data channel synchronously with the position requests that are controlled by the signal at the SYNC input of the frequency inverter cycle.

The process data channel is the fastest channel of the HIPERFACE DSL® protocol. Every protocol package transferred contains a complete update of the content of this channel.

This content consists of increments to rotation speed and fast position that are used as feedback parameters for the control loop of the motor drive (see sections 5.3.11 and 5.3.12).

If the fast position from the process data channel cannot be calculated (either due to transmission or due to sensor errors), estimation is made by the DSL Master based on the last two available position values of the Safe Channel. The worst case deviation from the actual mechanical position is also provided.

Because of the coding during the transfer of the process data channel, there is an upper range limit for both rotation speed and acceleration of the encoder shaft. These range limits are set out in Table 8 **and must be adhered to.**

2.2. Safe Channel

The safe position value of the motor feedback system is transferred on the Safe Channel as an absolute value. In addition, the status of the encoder is reported on this channel in the form of errors and warnings.

The safe position value transferred on the Safe Channel is not synchronous with the frequency inverter cycle signal at the SYNC input.

The safe position is used by the DSL Master IP Core to check the fast position value of the process data channel and can be used by the frequency inverter application for the same purpose.

Where there are deviations between the safe and the fast position values, an error message is generated (see section 6.6). In this case, the protocol replaces the fast position with the safe position.

In each package of the safe channel, a collection of status bits is transferred that reflects the error and warning condition of the motor feedback system.

It should be noted that each bit of the status byte of the Safe Channel consists of a collection of eight individual motor feedback system bits. Each separate status of the encoder can be selected with a "short message" (see section 6.6.1).

2.3. Safe Channel 2

In Safe Channel 2, the safe position value and the status of the motor feedback system secondary channel are transferred. The channel is for diagnostics in a safety oriented application.

The position value transferred on Safe Channel 2 is not synchronous with the frequency inverter cycle signal at the SYNC input.

The Safe Channel 2 is only available in the "safety" variants of the DSL Master IP Core.

The position value of Safe Channel 2 is either routed via a second processing channel in the DSL encoder (SIL2 system) or from a separate sensor source (SIL3 system).

In order to identify transmission errors or errors in the processing of the sensor signal, the user application must use the position value of Safe Channel 2 as a cross-check against the position value of the primary Safe Channel. The safety requirements are described in the HIPERFACE DSL® Safety Implementation Manual.

A status byte is transferred in each package of Safe Channel 2 that reflects the error and warning status of Channel 2 of the motor feedback system.

2.4. Parameters Channel

The Parameters Channel is the interface, over which the frequency inverter application reads and writes parameters of the motor feedback system.

In addition to the main task of position measurement, motor feedback systems with the HIPERFACE DSL® interface also have various internal resources installed. These resources are accessible via the Parameters Channel.

Examples of these resources are temperature measurements, monitoring - mechanisms for correct functioning, product data (the "electronic type label") or freely programmable data fields.

It should be noted that the resources actually installed for DSL products differ and are listed in the relevant product data sheet.

There are two types of communication on the Parameters Channel:

- "Short message" transaction
- "Long message" transaction

A "short message” transaction allows access to resources that have an influence on the HIPERFACE DSL® protocol interface and are used for monitoring them. This includes detailed status and error messages for the motor feedback system and indications of the signal strength on the DSL connection. As a "short message" transaction is processed directly by the interface logic of the motor feedback system, this transaction is completed in a comparatively short time.

A "long message" transaction allows access to all the other resources of the motor feedback system. Unlike a "short message" transaction, a "long message" normally requires processing by the motor feedback system processor and therefore has does not have a response time that can be defined in advance.

It should be noted that in HIPERFACE DSL®, a maximum of one "short message" and one "long message" are processed at any time.

2.5. SensorHub Channel

Data from additional external sensors can be transferred on the SensorHub Channel that can be used in the frequency inverter system. External sensors must be connected to the motor feedback system via the HIPERFACE DSL® SensorHub interface. Various sensors or sensor networks are accessible via this interface and can be selected using HIPERFACE DSL®.

The configuration of external sensors is carried out via the Parameters Channel, whilst the data are selected via the SensorHub Channel. The transfer of protocol packages in the SensorHub Channel takes place synchronously with the DSL transfer and as an extension of the frequency inverter cycle signal that is present at the DSL Master SYNC input. Depending on the use of the SensorHub interface, external data can therefore be sampled and transferred synchronously.

The protocol in the SensorHub Channel is not monitored by HIPERFACE DSL®. Apart from the monitoring of the data transfer quality, there are no protocol mechanisms on this channel.

A description of the SensorHub interface can be found in the HIPERFACE DSL® SensorHub manual.

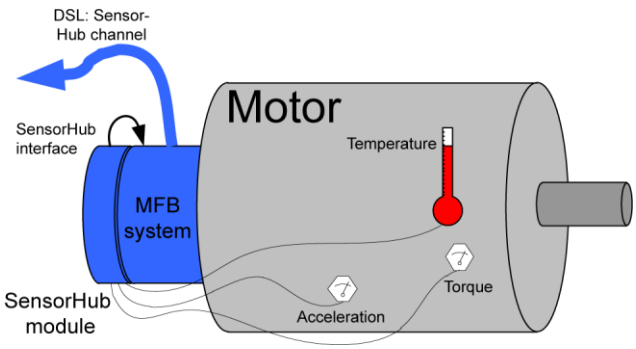


Figure 4: HIPERFACE DSL® SensorHub interface

3. Hardware installation

The installation of HIPERFACE DSL® in a drive system requires an interface circuit with special components as well as the installation of a digital logic core for an FPGA component.

The interface circuit is described thoroughly in this chapter. The chapter also contains recommendations for the selection of components.

The digital logic core (IP Core) is supplied by SICK for prescribed FPGA types.

In addition, the type of cable recommended for the connection between the frequency inverter and the motor feedback system is described thoroughly in this chapter.

It may also be possible to use other sorts of cable. These must be tested before use, however.

As a physical layer, HIPERFACE DSL® uses a transfer in accordance with EIA-485 (RS-485). Valid RS-485 interface drivers must comply with the conditions in Table 4.

Characteristic	Value	Units
Transfer rate	>20	MBaud
Permitted common mode voltage	-7 to +12	V
Receiver: Differential threshold voltage	< 200	mV
Load resistance	< 55	Ohm
Receiver running time delay	< 60	ns
Sender running time delay	< 60	ns
Sender power-up delay	< 80	ns
Sender power-down delay	< 80	ns
Sender rise time	< 10	ns
Sender dropout time	< 10	ns
Protection against short-circuit		
Protection against bus conflict		

Table 4: Valid RS-485 interface drivers

3.1. Interface circuit

HIPERFACE DSL® can be used in connection with two different interface circuit configurations. Each configuration requires a different sort of connection cable (see section 3.3).

Please note that the use of four core cable is no longer recommended for the motor cable.

3.1.1. Separate encoder cable - four core cable

When using a separate encoder cable (see section 3.3.1), the smallest interface circuit can be used. The separate encoder cable requires a four core connection.

In connection with the associated table, Figure 5 below gives the specification of the interface circuit.

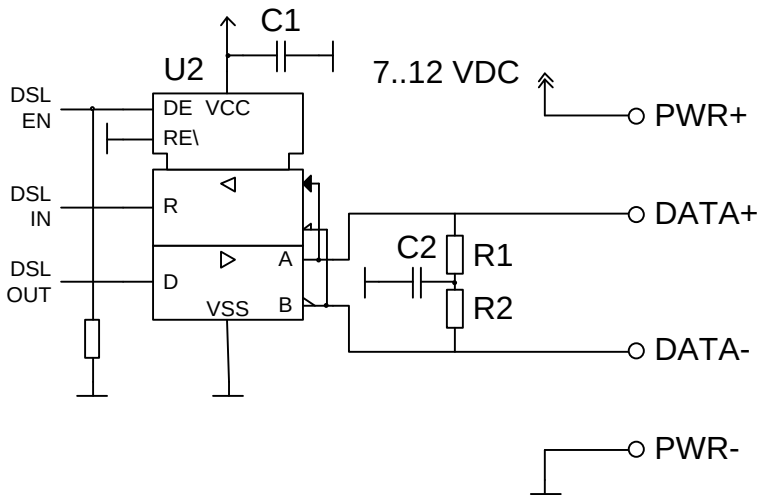


Figure 5: Interface circuit with separate encoder cable

Recommended components for the interface circuit are set out in Table 5

Component		Part	Manufacturer
C1	Ceramic capacitor	100 nF	
C2	Ceramic capacitor	2.2 µF, 16 V	
R1, R2	Resistors	56R	
U2	RS485 transceiver	SN65LBC176A SN75LBC176A MAX13431E	Texas Instruments Texas Instruments Maxim IC

Table 5: Components for the interface circuit with separate encoder cable.

3.1.2. Integrated cable - two core cable

For a connection via a two core cable integrated in the motor cable, (see section 3.3.2), the data cables must be provided with a transformer to raise the common mode rejection ratio. To feed the supply voltage into the data cables choke coils are also required.

In connection with the associated table, Figure 6 below gives the specification of the interface circuit.

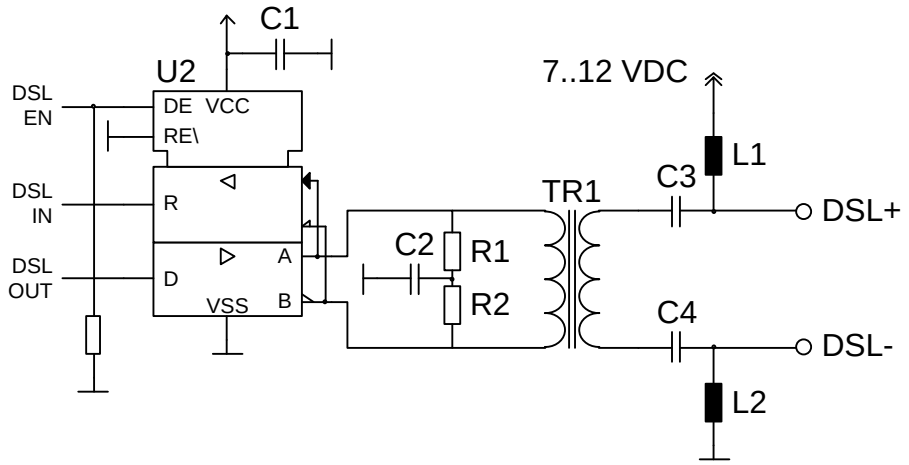


Figure 6: Interface circuit with two core cable (integrated in cable)

Recommended components for the interface circuit are set out in Table 6.

Component		Part	Manufacturer
C1	Ceramic capacitor	100 nF	
C2	Ceramic capacitor	2.2 µF, 16 V	
C3, C4	Ceramic capacitor	470 nF, 50 V	
L1, L2	Choke coils	B82462A2104K000, 100 µH ELL6SH101M, 100 µH	Epcos Panasonic
R1, R2	Resistors	56R	
U2	RS485 transceiver	SN65LBC176A SN75LBC176A MAX13431E	Texas Instruments Texas Instruments Maxim IC
TR1	Transformer	PE-68386NL 78602/1C B78304B1030A003 78602/1C	Pulse Engineering Murata Epcos Epcos

Table 6: Components of the interface circuit with two core cable (integrated in cable)

3.1.3. Motor feedback voltage supply

Motor feedback systems with HIPERFACE DSL® have been developed for operation with a supply voltage of 7 to 12 V. The voltage supply is measured at the encoder plug connector.

Table 7 below describes the specification for the power supply.

Parameter	Value
Switch-on voltage ramp	Max. 180 ms from 0 to 7 V
Inrush current	Max. 3.5 A (0 to100 µs) Max. 1 A (100 µs to 400 µs)
Operating current	Max. 250 mA at 7 V

Table 7: Voltage supply

3.2. FPGA IP Core

The frequency inverter system communicates with the DSL motor feedback system via a special protocol logic circuit that is designated as the DSL Master. The circuit is installed in an FPGA component and supplied by SICK. The circuit is supplied as an Intellectual Property Core (IP Core) along with a test circuit (test setup). The DSL Master IP Core is supplied in the form of a net list that can be freely connected within the FPGA. If there is sufficient space in the FPGA being used, the DSL Master can be installed in the same component as the frequency inverter application.

The IP Core is available as "safety" variant with a dual-channel interface to the frequency inverter or as a "standard" variant, which is smaller and has only one interface.

In order that various types of components - e.g. FPGA internal bus or an external processor - can be connected in the best way possible, various open source interface blocks are supplied with the IP Core. Details of the available interface blocks are set out in the IP Core manual (see Chapter 1.4).

The following figures show the possible combinations of IP Core and interface block variants.

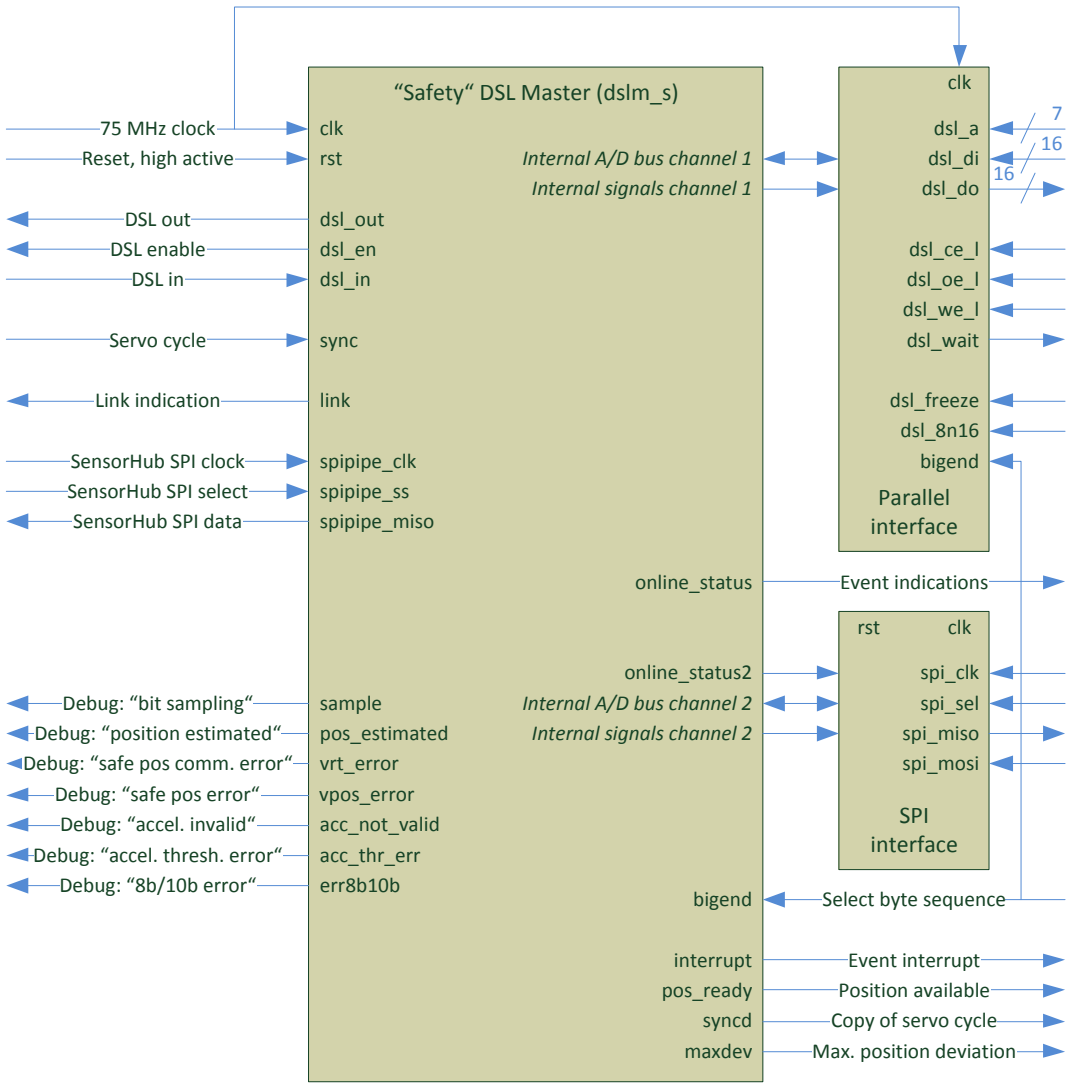


Figure 7: Block circuit diagram of the "safety" DSL Master IP Core with 1 parallel and 1 SPI interface.

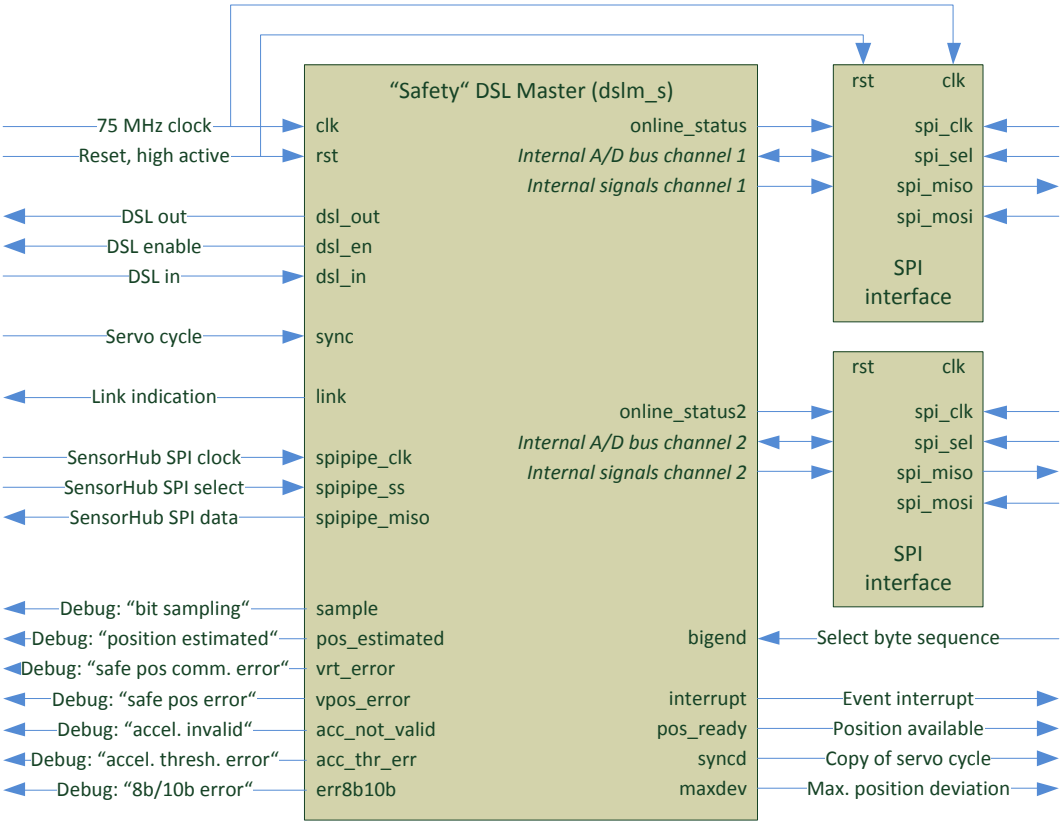


Figure 8: Block circuit diagram of the "safety" DSL Master IP Core with 2 SPI interfaces.

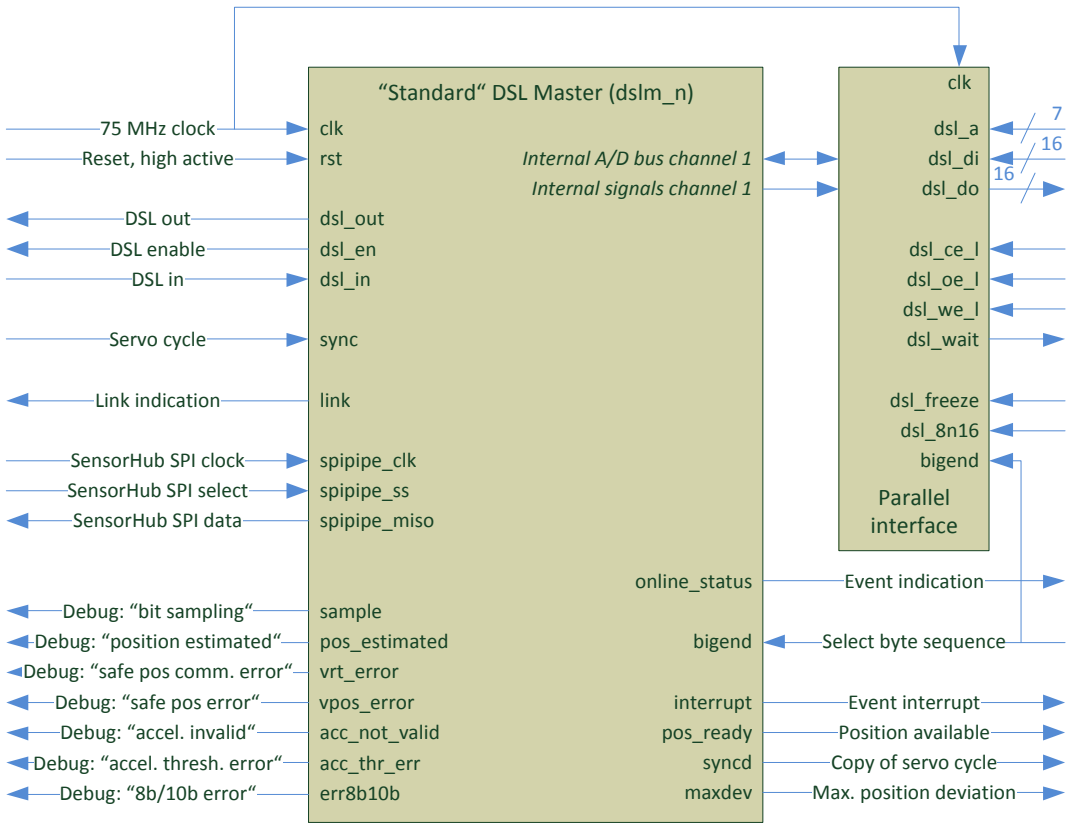


Figure 9: Block circuit diagram of the "standard" DSL Master IP Core with one parallel interface.

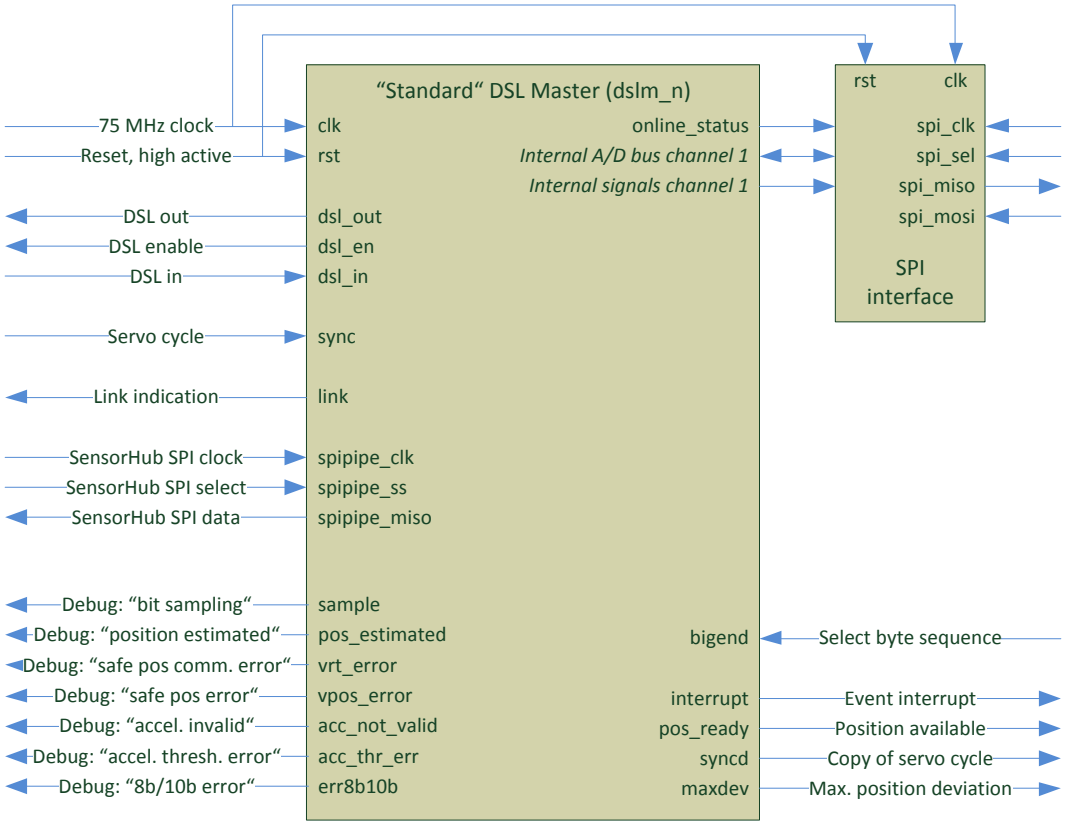


Figure 10: Block circuit diagram of the "standard" DSL Master IP Core with one SPI interface.

Parameter	Value			Units	Remarks
	Mini-mum	Typical	Maxi-mum		
System Clock	74.9925	75.0000	75.0075	MHz	± 100 ppm
Interface characteristics					
Cable transfer rate		9.375		MBd	
Reset duration	0.02	0.06		µs	Reset is High active
Recovery time after communication errors			727	µs	
Characteristics of the motor feedback system					
Position resolution per rotation		24	40	Bit	The total can be a maximum of 40 bits
Number of resolved rotations		16	40	Bit	
Rotation speed			262,000	rad/s	24 bit/rotation
Acceleration			670,000	rad/s²	24 bit/rotation
Sampling latency		10.1		µs	SYNC trigger up to valid position
Characteristics of the host interface					
Frequency inverter cycle time	12.1		1,950	µs	in SYNC mode
Frame cycle time	12.1		27	µs	in SYNC mode
Frame cycle time		11.52		µs	In free running mode
Duration of the SYNC signal	0.04			µs	The SYNC signal must be inactive for at least 0.04 µs per cycle.
Jitter of the SYNC signal frequency			2	%	In relation to package cycle time
Characteristics of the SPI-PIPE interface blocks					
SPI-PIPE clock			10	MHz	
Characteristics of the Parameters Channel					
Theoretical transfer rate	166		334	kBd	
Duration of access to the communications resource	167		1,100	µs	"Short message"
Duration of access to the encoder resource	263		764	µs	"Long message"
Characteristics of the SensorHub Channel					
Transfer rate	334		669	kBd	

Table 8: Characteristics of the DSL Master IP Core

3.2.1. DSL Master pin assignment

Table 9 below contains a description of the pin functions at the DSL Master IP Core.

Pin designation	Type	Function
rst	Input	Master reset (High active)
clk	Input	Clock input
sync	Input	Position sampling resolution
interrupt	Output	Configurable interrupt
link	Output	Connection indication
pos_ready	Output	Position data availability indication
syncd	Output	Position sampling resolution indication
bigend	Input	Byte sequence choice
dsl_in	Input	DSL cable, input data
dsl_out	Output	DSL cable, output data
dsl_en	Output	DSL cable transceiver, activation
spipipe_sel	Input	SensorHub SPI choice
spipipe_clk	Input	Serial clock for SPI SensorHub
spipipe_miso	Output	SPI SensorHub, master output data/slave input data

Table 9: Pin functions of the IP Core interface

Additional pin functions of the interface blocks are described in chapter 4.

3.2.2. Implementation of the IP Core

The implementation of the IP Core is described in the associated manual and is dependent on the choice of interface blocks and target technology (FPGA).

Chapter 1.4 lists the supporting documentation.

3.3. Cable specification

The cable recommended for connecting the frequency inverter to the HIPERFACE DSL® motor feedback system is specified by the parameters set out in Table 10. These technical data apply to all configurations.

In the case of integrated cables (see section 3.3.2), the motor cables are not listed.

Characteristic	Minimum	Typical	Maximum	Units
Length			100	m
Impedance at 10 MHz	100	110	120	Ω
DC loop resistance			0.1	Ω/m
Velocity ratio	0.66			c
Propagation delay		5		ns/m
Limit frequency	25			MHz
Maximum current per cable	0.25			A
Operating temperature	-40		125	°C

Table 10: Technical data for the HIPERFACE DSL® cable

3.3.1. Separate encoder cable - four core cables

The recommended cross section of the separate encoder cable with four encoder cables is given in Figure 11.

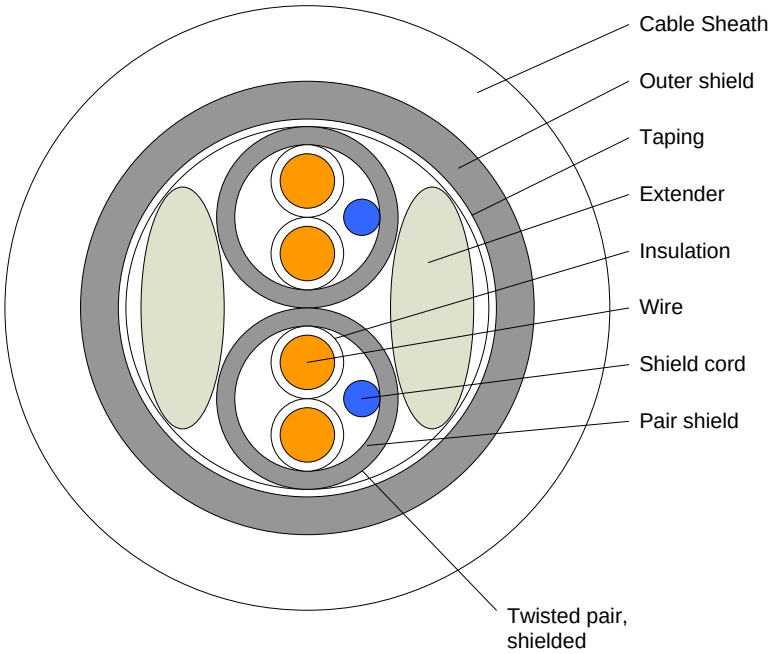


Figure 11: Cross section of the separate encoder cable with four encoder cables

3.3.2. Integrated cable - two core cable

The recommended cross section of the integrated cable with two encoder cables is given in Figure 12.

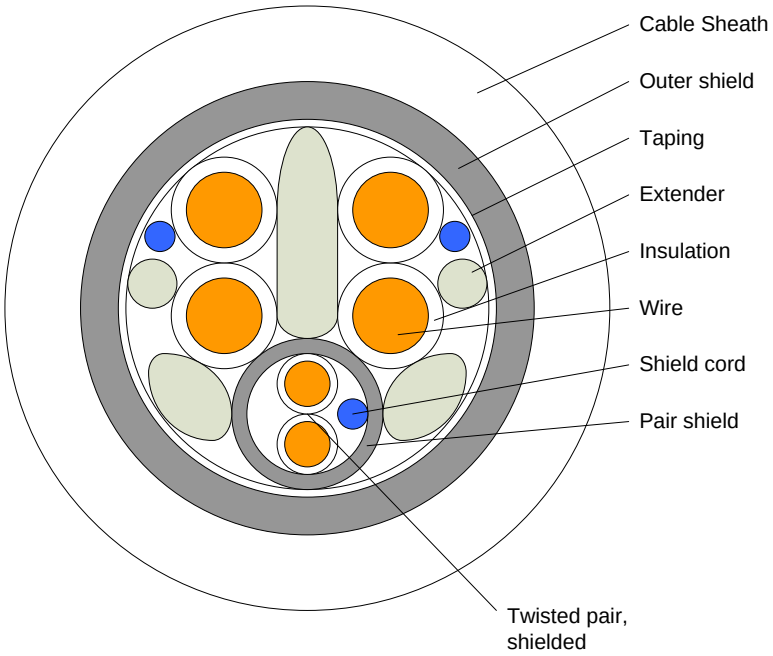


Figure 12: Cross section of the integrated cable with two encoder cables

More Informations relating cable construction and installation are available on the Whitepaper “Cable and Connector for HIPERFACE DSL® Motor and Drive Applications.

http://www.sick.com/group/EN/home/products/technologies/hiperfacedsl/Pages/hiperfacedsl_documentation.aspx

As a reference, the following manufacturers are listed.

Supplier	Article number
Helukabel	WT940060U
Leoni	95040129A
TecniKabel	35492

Table 11: Reference cables

4. Interfaces

The IP Core of the DSL Master includes interfaces to the motor feedback system (DSL Slave) and to the frequency inverter application (see Figure 13).

The motor feedback system communicates via a DSL connection with the DSL Master. All data channels between the DSL Master and DSL Slave are routed via this connection.

Depending on the use in safety-related applications, the frequency inverter is connected via one or two interfaces (choice of SPI or parallel bus) and several control signals. In addition, the frequency inverter provides a clock signal (CLK) and a reset signal (RST) to the DSL Master IP Core. By means of these signals, a defined start-up performance is achieved.

According to the requirements of the particular application, an optional serial interface (SPI-PIPE) can be employed to use the SensorHub Channel (see Section 2.5, SensorHub Channel).

The various interfaces correspond to the tasks described in Table 12.

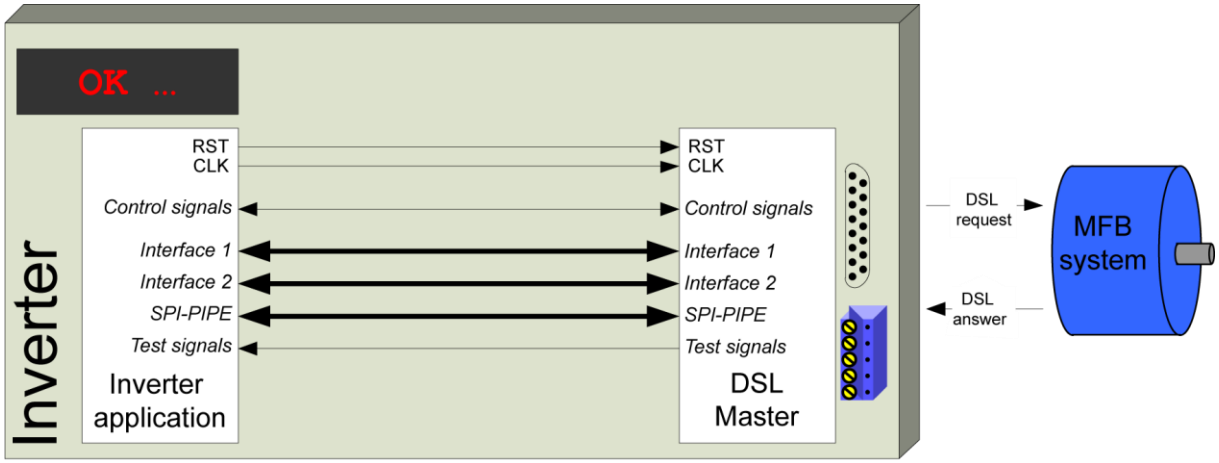


Figure 13: DSL system interfaces

Interface	Type	Function
Interface 1	Full duplex SPI -or- Parallel bus	Register-based access to all DSL Master and DSL Slave functions (except secondary position channel and optional SensorHub Channel)
Interface 2	Full duplex SPI	Register-based access to the DSL Master secondary position channel
SPI PIPE	SPI with read access	Optional register-based access to SensorHub Channel data
Control signals	Digital in/outputs	DSL Master indication and control signals
Test signals	Digital outputs	Test signals for development or fault-finding for a DSL controller
CLK	Digital input	Clock signal for the IP Core circuit
RST	Digital input	Reset signal for the IP Core circuit
DSL	Half duplex RS485	Connection to the motor feedback system

Table 12: Interface functions

4.1. Interface 1

Interface 1 forms the central communications interface between the frequency inverter application and the DSL Master IP Core. The Safe Channel position data can be read via this interface. The functions of the motor feedback system are also accessible via this interface.

Interface 1 is the only interface for Register Block 1 (see section 5.3).

If the "safety" variant of the DSL Master is used, Interface 1 is one of two channels for installing safety-related functions. In this case, the Safety Installation Manual must be followed.

The following signals are available via Interface 1:

Pin name	Model name	Function
online_status(0:15)	Output	IP Core status (see section5.2.1)
scan_a(0:6)	Input	Register address bus
scan_di(0:7)	Input	Register input data bus
scan_do(0:7)	Output	Register output data bus
scan_r	Input	Read signal
scan_w	Input	Write signal
scan_f	Input	Freeze signal

Table 13. Interface 1 signals.

Example installations of interface blocks for Interface 1 of the DSL Master are supplied together with the IP Core. These examples include a serial SPI interface and a parallel Texas Instruments EMIFA interface.

For safety installations, the use of one of the interface blocks supplied is highly recommended. Please refer to the safety manual for details.

4.2. Interface 2

Interface 2 forms the communications interface for the second channel between the frequency inverter application and the DSL Master IP Core. The secondary channel position data for safety-related functions can be read via this interface.

Interface 2 is the only interface for Register Block 2 (see section 5.4).

Interface 2 is only installed in "safety" variants of the DSL Master. In "standard" variants, Register Block 2 is not accessible.

The following signals are available via Interface 2:

Pin name	Model name	Function
online_status2(0:15)	Output	IP Core status (see section 5.2.2)
scan2_a(0:6)	Input	Register address bus
scan2_do(0:7)	Output	Register output data bus
scan2_f	Input	Stop signal

Table 14. Interface 2 signals.

DSL Master Interface 2 must be connected in accordance with the safety requirements of the Safety Installation Manual via a serial SPI interface.

4.3. SPI PIPE Interface

The SPI PIPE is a write-protected Serial Peripheral Interface (SPI). SPI PIPE is an optional communication channel between the frequency inverter application and the DSL Master IP Core. Read processes on the SensorHub Channel can be carried out via this interface. Alternatively, this data can also be read from the registers by standard transactions via Interface 1.

The type of access to the SensorHub Channel is selected by setting or deleting the **SPPE** bits in the **SYS_CTRL** register (see section 5.3.1). If the **SPPE** bit is deleted, the data and the status of the SensorHub channel are accessible via the DSL Master **PIPE_S** (2Dh) and **PIPE_D** (2Eh) registers. If the **SPPE** bit is set, the SensorHub Channel is read using the SPI PIPE "Read Pipeline" transaction.

SPI PIPE should be activated if, at a fast frequency inverter cycle, the bandwidth of Interface 1 is insufficient to access position and pipeline data, or if the pipeline data is being processed by another frequency inverter application resource.

It should be noted that in every case, the configuration of external sensor components at the SensorHub is carried out via the DSL Master Parameters Channel. The SPI PIPE provides only one read access to the SensorHub Channel (see section 2.5, SensorHub Channel).

The SensorHub Channel data is kept in a FIFO (First In First Out) buffer that can hold 8 bytes. In addition, for each data byte, status information is also stored in the FIFO buffer (see sections 5.3.21 and 5.3.22).

It should be noted that the FIFO buffer can only store 8 bytes of SensorHub Channel data. If the buffer is not read quickly enough, old data will be overwritten. This is indicated by a flag in the FIFO buffer status-information.

The SPI Master for the SPI PIPE is the frequency inverter application. The SPI functions "Slave Selection" (Pin: `spipipe_sel`) and "clock" (Pin: `spipipe_clk`) are controlled by the frequency inverter application. The SPI function "Data, Master input Slave output" (Pin: `spipipe_miso`) is controlled by the DSL Master.

SPI PIPE has the following SPI characteristics:

- PHA = 1 (Sampling for clock trailing edge, data changes for clock leading edge)
- POL = 0 (Basic clock value)

The data with the highest value bit (MSB) is given first.

When accessing the SensorHub Channel via the SPI PIPE, the first four bits of the status buffer (0101) show a different value for each transaction, in order to check the correct function of the interface.

4.3.1. SPI-PIPE timing

The time sequence for SPI PIPE is shown in the time sequence diagram (Figure 14) below and in Table 15.

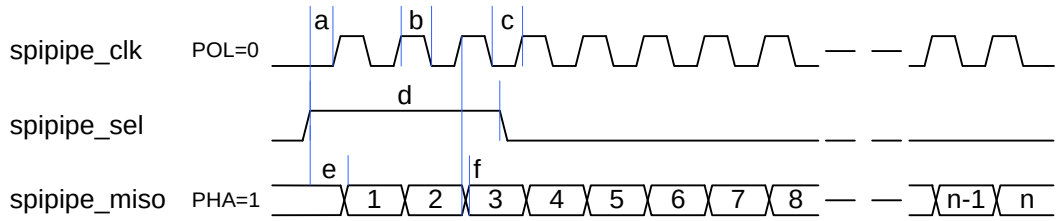


Figure 14: SPI-PIPE interface time control

Diagram reference	Description	Minimum	Maximum	Units
a	Creation of `spipipe_sel` before `spipipe_clk`	30		ns
b	Time for `spipipe_clk` high	30		ns
c	Time for `spipipe_clk` low	30		ns
d	`spipipe_sel` pulse width	30		ns
e	Delay `spipipe_miso` after `spipipe_sel` high	25	70	ns
f	Delay `spipipe_miso` after `spipipe_clk` high	25	70	ns

Table 15: SPI-PIPE time control

4.3.2. Read pipeline

The SPI PIPE transaction "Read Pipeline" is used for access to the FIFO buffer values that contain the data and status of the SensorHub Channel.

Symbol	Meaning
PIPE STATUS	SensorHub Channel status (see section 5.3.20)
PIPE DATA	SensorHub Channel data (see section 5.3.21)

Table 16: "Read Pipeline" transaction

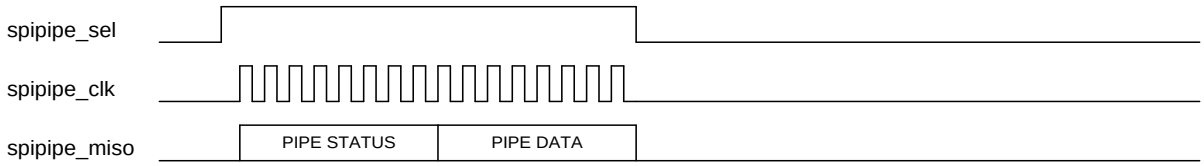


Figure 15: "Read Pipeline" transaction

4.4. Control signals

Various control signals are available between the DSL Master and the frequency inverter application to configure the performance of the IP Core or to carry out fast monitoring of the IP Core status.

4.4.1. SYNC signal

`sync` is a DSL Master digital input.

One edge on this pin triggers a position sampling. The polarity of the edge can be programmed using the **SPOL** bit in the **SYS_CTRL** (00h) register. The protocol requires a constant frequency of the signal at this pin, with deviations permitted within a set tolerance band. At start-up, the protocol synchronizes the protocol frame with the signal frequency at `sync`.

If the `sync` signal frequency is outside the tolerance range, re-synchronization of the protocol is triggered. During the time that the re-synchronization is taking place, sampling is carried out until the re-synchronization is complete with a signal generated by the DSL Master IP Core (also see section 6.3.2).

In this case it is guaranteed that the fast position data is not older than 30 µs and safe position data is not older than 240 µs.

4.4.2. INTERRUPT signal

`interrupt` is a DSL Master digital output.

`interrupt` is set to "1" if an interrupt condition has been fulfilled in the DSL-Master. The interrupt conditions are set using the registers **MASK_H**, **MASK_L** and **MASK_SUM** (see sections 5.3.5 and 5.3.6).

During each write process in one of the registers **EVENT_H** or **EVENT_L**, the `interrupt` output is triggered until the current SPI transaction has ended.

4.4.3. LINK signal

`interrupt` is a DSL Master digital output.

`link` reflects the content of the LINK bit in the **MASTER_QM** register (see section 5.3.3) and therefore indicates whether the DSL Master has produced a communications link to a connected HIPERFACE DSL® motor feedback system.

`link` is intended to be a control signal for an LED display, but can also be used to control the start-up performance (see section6.1) or for global error handling.

`link` is reset if communication faults are detected.

4.4.4. POS_READY signal

pos_ready is a DSL Master digital output.

pos_ready gives the time point for availability of the position values and permits an event-based reading of the position for incorporating latency reduction.

A rising edge at pos_ready indicates that the fast and safe positions are available from Channel 1. A falling edge indicates that the safe position is available from Channel 2.

pos_ready is always available, even if the position value is invalid or no connection to the encoder has been established.

The time control is Figure 16 illustrated below.

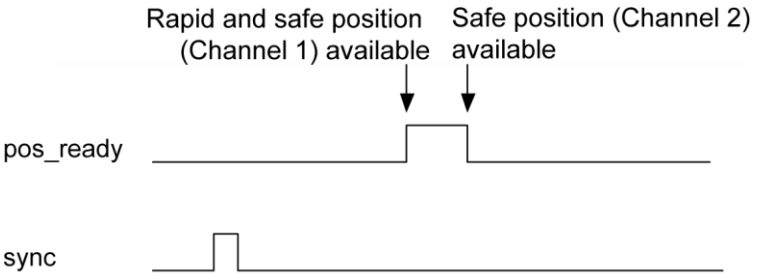


Figure 16: pos_ready indications.

Dependent upon the configuration in the register system control (see section 5.3.1), pos_ready displays either only the availability of positions based on user requirements (edge at sync input) or all transmitted positions.

4.4.5. SYNCD signal

syncd is a DSL Master digital output.

syncd indicates whether the sync signal was correctly passed to the encoder, or whether the IP Core is still in a synchronization phase. syncd has the value "1" if the offset between the sync signal and sampling edge is shorter than two clock cycles, otherwise "0".

4.4.6. BIGEND signal

bigend is a DSL Master digital input.

The byte sequence of the address allocation for registers can be influenced via bigend (see section 5.3, 5.4). The byte sequence is based on 32 bit-wide data words. The selection influences the allocation independently of the interface block used.

Table 17 below lists the selection options for bigend.

Value	Address allocation byte sequence
0	Little endian
1	Big endian

Table 17: bigend selection.

4.4.7. MAXDEV signal

`maxdev` is a DSL Master digital output.

If the fast position from the process data channel cannot be calculated (either due to transmission or due to sensor errors), estimation is made by the DSL Master based on the last two available position values of the Safe Channel. The worst case deviation from the actual mechanical position is also provided, referring to a user-defined parameter for the maximum possible acceleration in the application (fast position acceleration boundary, see ch. 5.3.24).

A threshold can be set up for a worst case deviation to raise the `maxdev output`. The threshold is a user-defined parameter for the maximum tolerable deviation in the application (fast position estimator deviation, see ch. 0).

`maxdev` indicates whether the maximum tolerable deviation is violated (‘1’) or kept (‘0’).

4.5. Reset

`rst` is the reset input of the DSL Master IP Core.

After start-up (switching on) of the frequency inverter, a reset procedure is mandatory to return the DSL Master IP Core to its initialization condition.

The reset procedure is established by the parameters listed in Table 18 and quoted in Figure 17.

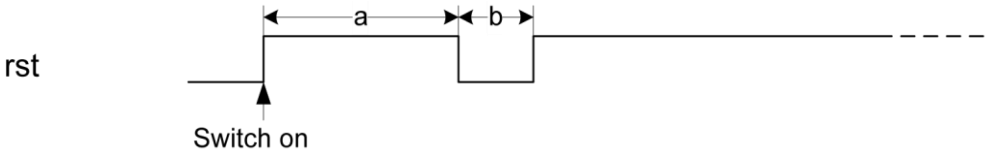


Figure 17: Reset procedure

Diagram reference	**Parameters in** Table 8	**Value (cf.** Table 8**)**
a	Reset delay	Variable
b	Duration of the reset signal	>60 ns

Table 18: Reset time sequence.

4.6. Test signals

To support development or fault-finding for controllers that have a DSL interface integrated, the DSL Master supplies some test signals.

4.6.1. SAMPLE signal

`sample` is a DSL Master digital output.

The `sample` signal is set at the sampling time point of each bit that is transmitted from the DSL motor feedback system. It consists of 50 pulses from Channel 1 followed by a bit pause and 10 pulses from Channel 2 of the motor feedback system.

Figure 18: Sample signal

The `sample` signal can be used for eye diagrams to measure time and voltage margins during signal transmission.

When making the evaluation, signal delays in the DSL Master must be taken into account. The rising edge of the `sample` signal is offset by 40 ns from the line driver signal. The time delay of the line driver must also be taken into account. Typically this is 13 ns.

4.6.2. POS_ESTIMATED signal

`pos_estimated` is a DSL Master digital output.

The `pos_estimated` signal is set if some event leads to the fast position (see 5.3.11) being invalid and the position estimator supplying the values. Such events are:

- The DSL motor feedback system reporting a position error
- A coding error in transmission of the fast position
- A check-sum error in transmission of the fast position
- Realignment from fast to safe position
- The protocol is re-synchronizing following a break in the link

The `pos_estimated` signal can be used to carry out a statistical analysis of the incidence of errors in the DSL system.

4.6.3. VRT_ERROR signal

`vrt_error` is a DSL Master digital output.

The `vrt_error` signal is set if some event leads to the safe position (see 5.3.14) being invalid. Such events are:

- A coding error in transmission of the safe position
- A check-sum error in transmission of the safe position

The vrt_error signal can be used to carry out a statistical analysis of the incidence of errors in the DSL system.

4.6.4. VPOS_ERROR signal

vpos_error is a DSL Master digital output.

The vpos_error signal is set if the safe position is not updated or it has never been written since the startup due to a fault of the internal address/data bus.

4.6.5. ACC_NOT_VALID signal

acc_not_valid is a DSL Master digital output.

The acc_not_valid signal is set if an encoding error was detected after transmission of a fast position value.

If the acc_not_valid signal is set the error counter acc_err_cnt will be incremented with each transmission (see **Fehler! Verweisquelle konnte nicht gefunden werden.**). As soon as the acc_not_valid signal is reset the error counter acc_err_cnt will be set to “0”.

4.6.6. ACC_THR_ERR signal

acc_thr_err is a DSL Master digital output.

The acc_thr_err signal is set if the threshold programmed in register acc_err_cnt is exceeded.

The acc_thr_err signal can be used to implement a fault-tolerant evaluation in the drive. For this the maximum position deviation can be calculated from the number of transmission errors.

4.6.7. ERR8B10B signal

err8b10b is a DSL Master digital output.

The err8b10b signal is set if the underlying 8B/10B encoding of a DSL frame transmission is disturbed.

The err8b10b signal can be used to make a statistical analysis of the bit error rate of a DSL system.

5. Register diagram

The DSL Master is accessible via the register in two different register blocks. Each register block has its own address area (see Table 19).

Register block	Address area	Functions
1	00h to 7Fh	Channel 1, position/status Parameters Channel SensorHub Channel
2	00h to 3Fh	Channel 2, position/status

Table 19: Register blocks address area.

Transactions with the DSL Master registers are carried out by the appropriate read and write operations via either Interface 1 or Interface 2. Optionally, the SensorHub Channel data is accessible via SPI PIPE.

In addition, the DSL Slave interface registers are mirrored as decentralized registers in Register Block 1. The address area 40h to 7Fh is intended for this. The addressing of this register is identical to the addressing of the register in the DSL Master. The answer to the transaction is, however, delayed and must be read individually (see under "Short message", in Section 6.6.1).

Figure 19 below shows via which interface a connection to which register block is established.

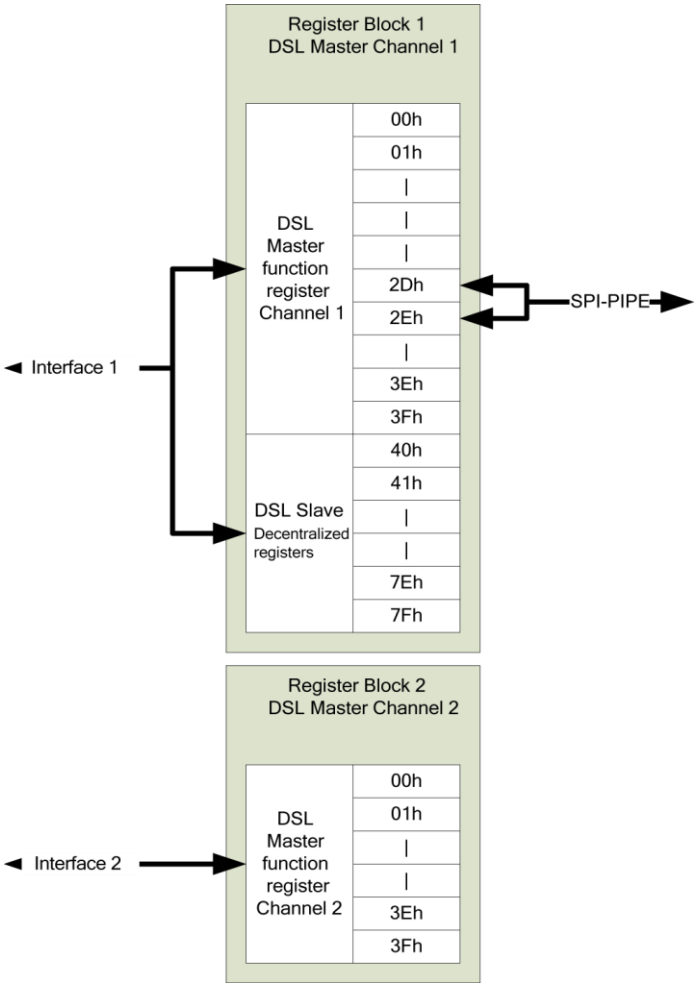


Figure 19: Register block interfaces

5.1. Explanation of the registers

In the following description of the registers, symbols are used to describe the standard value of a bit following a reset. Additional symbols are used to describe the functions provided to the frequency inverter application for this bit.

The bit is described according to the following sample:

"Function" "Reset value", e.g. "R/W-0"

Function symbol	Meaning
R	Bit can be read.
W	Bit can be set and deleted.
C	Bit can only be deleted.
X	Bit is not installed and will always be read as "0".

Table 20: Function symbols for bits

Reset value	Meaning
0	The bit is deleted after a reset.
1	The bit is set after a reset.
x	After a reset, the bit has no defined value.
-	In the register diagram: The bit is not installed and will always be read as "0".

Table 21: Symbols for bit reset values

It should be noted that read access to a bit that can only be described ("W") always returns the value "0".

5.2. Online Status

For each of Interfaces 1 and 2, there is a group of event indicators available. These indicators display events, warnings or errors that are not stored.

5.2.1. Online Status 1

In Interface 1, the Online Status is a non-storing copy of registers **EVENT_H** and **EVENT_L**. The static information in these registers must be deleted by the user after the read process, by writing the value "0" to the corresponding bit in the register, whilst the Online Status only shows the current status without storing previous indications.

Online Status 1 is given in two bytes. If the SPI interface block is used, Online Status 1 is transmitted in each transaction in the first two bytes over the `spi_miso` cable. When the parallel bus interface is used at Interface 1, Online Status 1 has 16 dedicated output signals available.

It should be noted that when the parallel bus interface is used the 16 signals of the Online Status are not frozen during a read access. If required, the user can insert a Latch (e.g. `scan_f` signal).

All error indications in High Byte are potentially critical and safety-related. Suitable measures must be installed in the user application.

All error indications in Low Byte relate to non safety-related errors or warnings.

Online Status 1, High Byte

R-0	R-0	R-0	R-1	R-0	R-0	R-0	R-0
INT	SUM	VRT	FIX1	POS	VPOS	QMLW	PRST
Bit 7							Bit 0

Bit 7 **INT**: Status of the Interrupt output
This bit represents an exception to the Online Status, as this bit does not relate to an event indication. INT provides the value of the physical INT output so that request management (polling) can be established. The importance of this flag depends on the Interrupt sources monitored.
1 = `interrupt` output on "High" level
0 = `interrupt` output on "Low" level

Bit 6 **SUM**: Summary byte
1 = The last valid value from **SUMMARY** was not zero. The importance of this flag depends on the particular error source that leads to a set **SUMMARY** (see section 5.3.13).
0 = The last valid value from **SUMMARY** was zero.

Bit 5 **VRT:** CRC error on the Safe Channel
1 = The last Safe Channel CRC received in Channel 1 was wrong. It is probable that the safe position transmitted from Channel 1 (see section 2.2) is invalid. **Suitable measures must be installed in the user application.**
0 = The last vertical CRC received in Channel 1 was correct.

Bit 4 **FIX1**: This bit always gives a "1". For SPI interfaces, this is used for checking the `spi_miso` pin for stuck-at- '0' faults.

Bit 3 **POS**: Fast position invalid
1 = A source of an error in the fast position in Channel 1 was identified or an alignment procedure is currently being carried out. It is probable that the last fast position is invalid. This error is not safety-related, provided the value is within the range limits defined for the DSL system safety functions. In each case, appropriate measures for handling fast position errors must be implemented in the user application.
0 = No fast position error identified in Channel 1.

Bit 2 **VPOS**: Safe position invalid
1 = A source of an error in the safe position in Channel 1 was identified. It is probable that the safe position transmitted from Channel 1 (see section 2.2) is invalid. **Suitable measures must be implemented in the user application.**
0 = The last safe position received in Channel 1 was correct.

Bit 1 **QMLW**: Quality monitoring at Low level (see section 5.3.3)
1 = Current value of quality monitoring less than 14.
0 = Current value of quality monitoring greater than or equal to 14.

Bit 0 **PRST**: Protocol reset
1 = IP-Core has restarted the protocol.
0 = IP-Core running.

Online Status 1, Low Byte

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
POSTX		MIN	ANS	FIX0	RET	FREL	FRES
Bit 7							Bit 0

Bit 7-6 **POSTX1:POSTX0**: Position transmission status
00: Position request is transmitted to the DSL encoder.
01: Safe Channel was correctly transmitted.
10: Fast position present (see section 5.3.11).
11: Safe Channel 2 was correctly transmitted.

Bit 5 **MIN**: Acknowledgment of message initialization
1 = The DSL encoder sends a figure by which the initialization of the Parameter Channel is acknowledged.
0 = Parameter Channel not functioning.

Bit 4 **ANS**: Incorrect answer detected.
1 = The last answer to a long message was damaged.
0 = No error detected in the last answer to a long message.

Bit 3 **FIX0**: This bit always gives a "0". For SPI interfaces, this is used for checking the `spi_miso` pin for stuck-at-'1' faults.

Bit 2 **RET**: Retry attempt at a "long" or "short" message
1 = An attempt has just been made to resend a "long" or "short" message.
0 = No attempt is made to send a "long" or "short" message.

Bit 1 **FREL**: Channel status for “long message”.
1 = The channel for the “long message” is free.
0 = The channel for the “long message” is in use.

Bit 0 **FREL**: Channel status for the "short message".
1 = The channel for the "short message" is free.
0 = The channel for the "short message" is in use.

5.2.2. Online Status 2

At Interface 2, Online Status 2 provides information about Channel 2 of the DSL encoder. The data always indicate the current status, with previous indications not being stored.

Online Status 2 is given in two bytes. If the SPI interface block is used, Online Status 2 is transmitted in each transaction in the first two bytes over the `spi_miso` pin.

CAUTION

All fault indications in Online Status 2 are potentially critical and safety-related. Suitable measures must be installed in the user application.

Online Status 2, High Byte

X-0	R-0	R-0	R-1	X-0	R-0	R-0	R-0
-	SUM2	COM2	FIX1	-	POS2	QMLW	PRST
Bit 7							Bit 0

Bit 7 **Not implemented**: Read as "0".

Bit 6 **SUM2**: Summary byte Channel 2
1 = One of the indications **TEST2** or **ERR2** is set (see section 5.4.2). The error reaction to this flag depends on the meaning of the bit they are based on.
0 = Neither **TEST2** nor **ERR2** is set.

Bit 5 **COM2**: Transmission error Channel 2
1 = The last data received in Channel 2 contains a transmission error. It is probable that the safe position transmitted from Channel 2 (see section 2.3) is invalid. **Suitable measures must be installed in the user application.**
0 = The last data received in Channel 2 was correct.

Bit 4 **FIX1**: This bit always gives a "1". For SPI interfaces, this is used for checking the `spi_miso` cable for stuck-at-'0' faults.

Bit 3 **Not implemented**: Read as "0".

Bit 2 **POS2:** Safe position Channel 2 invalid
1 = A source of an error in the safe position in Channel 2 was identified. It is probable that the safe position transmitted from Channel 2 (see section 2.3) is invalid. **Suitable measures must be installed in the user application.**
0 = The last safe position received in Channel 2 was correct.

Bit 1 **QMLW**: Quality monitoring at Low level (see section 5.3.3)
1 = Current value of quality monitoring less than 14.
0 = Current value of quality monitoring greater than or equal to 14.

Bit 0 **PRST**: Protocol reset
1 = Protocol control unit is rebuilding the stack.
0 = Protocol control unit not functioning.

Online Status 2, Low Byte

R-0	R-0	X-0	X-0	R-0	X-0	X-0	X-0
POSTX		-	-	FIX0	-	-	-
Bit 7							Bit 0

Bit 7-6 **POSTX1:POSTX0**: Position transmission status
POSTX indicates whether a requested position was transmitted.
00: Position request is transmitted to the DSL encoder.
01: Safe Channel was correctly transmitted.
10: Fast position present (see section 5.3.11).
11: Safe Channel 2 was correctly transmitted.

Bit 5-4 **Not implemented**: Read as "0".

Bit 3 **FIX0**: This bit always gives a "0". For SPI interfaces, this is used for checking the `spi_miso` cable for stuck-at-'1' faults.

Bit 2-0 **Not implemented**: Read as "0".

5.3. DSL Master function register on Channel 1

The protocol logic controls the non-safety-related performance of the DSL Master via the registers in the DSL Master IP Core on Channel 1. In addition, these registers are also used for accessing the position values of Channel 1.

Table 22 contains a list of these registers on Channel 1.

Addr	Designation	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Value at reset
00h	SYS_CTRL	PRST	MRST	FRST	LOOP	PRDY	SPPE	SPOL	OEN	0000 0000
01h	SYNC_CTRL	ES								0000 0001
03h	MASTER_QM	LINK	-	-	-	Quality monitoring				0--- 0000
04h	EVENT_H	INT	SUM	VRT	-	POS	VPOS	QMLW	PRST	001- 0010
05h	EVENT_L	-	-	MIN	ANS	-	RET	FREL	FRES	--00 -000
06h	MASK_H	-	MSUM	MVRT	-	MPOS	MVPOS	MQMLW	MPRST	-00- 0000
07h	MASK_L	-	-	MMIN	MANS	-	MRET	MFREL	MFRES	--00 -000
08h	MASK_SUM	MSUM7:0								0000 0000
09h	EDGES	Bit sampling pattern								0000 0000
0Ah	DELAY	RSSI				Cable delay				0000 0000
0Bh	VERSION	Coding		IP Core version number						0100 0001
0Dh	ENC_ID2	-	SCI			ENC_ID19:16				-000 0000
0Eh	ENC_ID1	ENC_ID15:8								0000 0000
0Fh	ENC_ID0	ENC_ID7:0								0000 0000
10h	POS4	Fast position, byte 4								0000 0000
11h	POS3	Fast position, byte 3								0000 0000
12h	POS2	Fast position, byte 2								0000 0000
13h	POS1	Fast position, byte 1								0000 0000
14h	POS0	Fast position, byte 0								0000 0000
15h	VEL2	Speed, byte 2								0000 0000
16h	VEL1	Speed, byte 1								0000 0000
17h	VEL0	Speed, byte 0								0000 0000
18h	SUMMARY	SUM7:0								0000 0000
19h	VPOS4	Safe position, byte 4								0000 0000
1Ah	VPOS3	Safe position, byte 3								0000 0000
1Bh	VPOS2	Safe position, byte 2								0000 0000
1Ch	VPOS1	Safe position, byte 1								0000 0000
1Dh	VPOS0	Safe position, byte 0								0000 0000
1Eh	VPOSCRC_H	CRC of the safe position, byte 1								0000 0000
1Fh	VPOSCRC_L	CRC of the safe position, byte 0								0000 0000
20h	PC_BUFFER0	Parameters Channel, byte 0								0000 0000
21h	PC_BUFFER1	Parameters Channel, byte 1								0000 0000
22h	PC_BUFFER2	Parameters Channel, byte 2								0000 0000
23h	PC_BUFFER3	Parameters Channel, byte 3								0000 0000
24h	PC_BUFFER4	Parameters Channel, byte 4								0000 0000
25h	PC_BUFFER5	Parameters Channel, byte 5								0000 0000
26h	PC_BUFFER6	Parameters Channel, byte 6								0000 0000
27h	PC_BUFFER7	Parameters Channel, byte 7								0000 0000
28h	PC_ADD_H	LID	LDIR	LOFF	LIND	LLEN		LADD9:8		1000 0000
29h	PC_ADD_L	LADD7:0								0000 0000
2Ah	PC_OFF_H	LID	LOFFADD14:8							1000 0000
2Bh	PC_OFF_L	LOFFADD7:0								0000 0000
2Ch	PC_CTRL	-	-	-	-	-	-	-	LSTA	---- ---0
2Dh	PIPE_S	-	-	-	-	POVR	PEMP	PERR	PSCI	---- 0000
2Eh	PIPE_D	SensorHub FIFO, output								0000 0000
2Fh	PC_DATA	"Short message" data								0000 0000
38h	ACCERR_CNT	-	-	-	Acc. error threshold/counter					---0 0000
39h	MAXACC	Acc. Res.		Acc. Mantissa						0000 0000
3Ah	MAXDEV_H	Max. position deviation, byte 1								1111 1111
3Bh	MAXDEV_L	Max. position deviation, byte 0								1111 1111
3Fh	DUMMY	No data								---- ----

Table 22: Description of the registers in DSL Master, Channel 1

5.3.1. System control

The system control register SYS_CTRL contains the main control bits of the DSL Master.

It should be noted that apart from a reset of the Master, all system control bits can only be set and deleted by the user.

Register 00h: **System control**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
PRST	MRST	FRST	LOOP	PRDY	SPPE	SPOL	OEN
Bit 7							Bit 0

Bit 7 **PRST**: Protocol reset
1 = A forced reset of the protocol status will be initiated. If the bit is deleted, a restart of the connection is triggered.
0 = Normal protocol action

Bit 6 **MRST**: Messages reset
1 = The Parameters Channel is reset. Current short and long messages are discarded.
0 = Normal Parameters Channel action

Bit 5 **FRST**: Pipeline FIFO, reset
1 = The FIFO is reset. Data is not stored and cannot be read.
0 = Normal FIFO access

Bit 4 **LOOP:** Test Interface 1
Value for the read back test for Interface 1. This value has no other purpose.

Bit 3 **PRDY**: POS_READY mode (see section 4.4.4).
1 = pos_ready shows time of receipt of all position transmissions.

0 = pos_ready shows only the time of receipt of position transmissions following a control clock (sync input).

Bit 2 **SPPE**: SPI-PIPE activation
1 = SPI-PIPE activated. Access to pipeline status and data via SPI-PIPE. The registers **PIPE_S** and **PIPE_D** are read as "0".

0 = SPI-PIPE deactivated. Access to pipeline status and data via the registers **PIPE_S** and **PIPE_D**.

Bit 1 **SPOL**: Polarity of the synchronization pulse
1 = The sync trailing edge is used.
0 = The sync leading edge is used.

Bit 0 **OEN**: Activation of the output
1 = The DSL cables are activated for output to the DSL Slave.
0 = The impedance of the DSL cable is high.

5.3.2. Synchronization control

The SYNC_CTRL register for control of the synchronization contains the bit with which the synchronization source for position sampling is controlled.

Register 01h: **Synchronization control**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-1
ES							
Bit 7							Bit 0

Bit 7-0 **ES**: External synchronization
00000000 = Position sampling during free running at the shortest cycle time.
All other values = Position sampling with the sync signal synchronized. The value from **ES** determines the number of position samplings carried out in one sync cycle. The user must match the number of samplings per cycle to the shortest frame length (see section 6.3.2).

5.3.3. Quality monitoring

The MASTER_QM quality monitoring register contains the quality monitoring value for the data connection.

As soon as the DSL Master registers events that indicate an improvement or degradation of the quality of the data connection, these events are indicated as values higher or lower than the quality monitoring value (see Table 23).

Protocol event	Value change in quality monitoring
Wrong synchronization in Safe Channel (last byte)	-4
Wrong synchronization in Safe Channel (1st … 7th bytes)	-6
RSSI <1	-4
Wrong encoding in parameter or SensorHub channels	-1
Wrong encoding in process data channel	-2
Unknown special characters in the protocol package	-2
Any identified error in Safe Channel 1	-6
Any identified error in Safe Channel 2	-8
Correct synchronization in Safe Channel	+1
Correct CRC value in Safe Channel	+1

Table 23: Quality monitoring events

Quality monitoring is initiated with the value "8".

The maximum quality monitoring value is "15". This is the standard value during operation.

Particular attention must be paid to the quality monitoring value during the development of a DSL drive controller. If a value lower than "15" is indicated, the cause may be a problem with the connection circuit, particularly if the value is continuously displayed.

If the quality monitoring value falls below "14", **QMLW** information is indicated in Online Status 1 and in the **EVENT_H** register.

If the quality monitoring value falls to "0", a forced reset of the protocol is carried out. This is indicated by the **PRST** error bit in Online Status 1 and in the **EVENT_H** register.

The `MASTER_QM` register is write protected.

Register 03h: **Quality monitoring register**

R-0	X-0	X-0	X-0	R-0	R-0	R-0	R-0
LINK				QM			
Bit 7							Bit 0

Bit 0 **LINK**: DSL protocol connection status
1 = Protocol connection between DSL Master and Slave was established.
0 = No connection present or connection error due to a communications error.

It should be noted that **LINK** is also represented at the `link` interface output (see section 4.4.3).

Bit 6-4 **Not implemented**: Read as "0".

Bit 3-0 **QM3:QM0**: Quality monitoring bits
0000 to 1111: Quality monitoring value. Higher values indicate a better connection. If the quality monitoring reaches the value "0000", a forced reset of the protocol is carried out.

5.3.4. Events

The EVENT_H/EVENT_L registers contain the messaging bits for all warning and error modes of the DSL system.

All messaging bits are set by the DSL Master if a corresponding status is determined.

The following bit description lists the effects of warning and error conditions as well as the reactions to errors that must be installed in the frequency inverter application.

An event bit that has been set is not reset by the DSL Master. The frequency inverter application must delete bits that have been set.

Both edge and level-sensitive flags are present in the EVENT registers. Edge-sensitive bits are set when the corresponding status arises. They are only set again if the corresponding status disappears and then arises once more. This is the standard action. The level-sensitive bits set a bit as long as the corresponding status exists.

It should be noted that all event register bits are also transferred to Online Status 1 (see section 5.2.1). The event bits are not static there and contain the actual status of each individual event.

Register 04h: **High Byte events**

R-0	R/C-0	R/C-1	X-0	R/C-0	R/C-0	R/C-1	R/C-0
INT	SUM	VRT		POS	VPOS	QMLW	PRST
Bit 7							Bit 0

Bit 7 **INT**: Interrupt status
This bit reflects the status of the interrupt signal (see section 4.4.2).

Bit 6 **SUM**: Remote event monitoring
1 = The DSL Slave has signaled an event and the summary mask is set accordingly (see registers MASK_SUM and SUMMARY).
0 = All DSL Slave events are deleted.
When the **SUM** bit is set, an error or a warning has been transmitted from the DSL Slave. The frequency inverter application must check the SUMMARY register (see section 5.3.13) to obtain a detailed description. This bit is level sensitive.

Bit 5 **VRT:** Error on the Safe Channel
1 = Data consistency error on the Safe Channel.
0 = Safe Channel data was correctly transmitted.
This error usually indicates a transmission error on the DSL connection. If this error occurs frequently, the wiring of the DSL connection should be checked. If this error occurs continuously, there is probably an error in the motor feedback system.
This error affects quality monitoring and produces the **QMLW** warning or a protocol reset.

CAUTION

When this error occurs, the last valid value of the safe position is retained (see section 5.3.14). Only if a fresh value has been transmitted will the safe position be updated and correspond to the actual position of the motor feedback system. The fast position is not affected by this.

Bit 4 **Not implemented**: Read as "0".

Bit 3 **POS**: Fast position error
1 = Fast position data consistency error
0 = The data for the fast position was correctly transmitted.
This error usually indicates a transmission error on the DSL connection. If this error occurs frequently, the wiring of the DSL connection should be checked. If this error occurs continuously, there is probably an error in the motor feedback system.

CAUTION

When this error occurs, the fast position is updated by an extrapolation. The last valid rotation speed value is used for this extrapolation. Only if a new valid safe position has been transmitted (see section 5.3.14) is the fast position updated to the actual position of the motor feedback system. This can lead to a temporary (<200 µs) difference between the actual and the transmitted position, particularly during accelerated movement of the drive.

Bit 2 **VPOS**: Safe position error, Channel 1
1 = Sensor error in Channel 1.
0 = The safe position is correct.
This error usually indicates an encoder sensor error. If this error occurs continuously, there is probably an error in the motor feedback system.

CAUTION

When this error occurs, the error value FD FD FD FD FDh is displayed instead of the safe and fast position in Channel 1.

Bit 1 **QMLW**: Quality monitoring low value warning
1 = Quality monitoring value (see register 03h) below "14"
0 = Quality monitoring value greater than or equal to "14"

This warning indicates that a transmission error occurred at bit level for one of the CRC values. If this error occurs frequently, the wiring of the DSL connection should be checked (also see section 5.3.3).

Bit 0 **PRST**: Protocol reset warning
1 = The forced protocol reset was triggered.
0 = Normal protocol action
This error message indicates that the protocol connection to the DSL Slave has been re-initialized. This error message can be caused by a frequency inverter application request (**PRST** bit in `SYS_CTRL`), generated by the DSL Master itself, or activated via the `rst` input.
The DSL Master causes a protocol reset if too many transmission errors indicate a connection problem (see section 5.3.3). A protocol reset causes a re-synchronization with the DSL Slave that can improve the connection quality.

Register 05h: **Low Byte events**

X-0	X-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
		MIN	ANS		RET	FREL	FRES
Bit 7							Bit 0

Bit 7-6 **Not implemented**: Read as "0".

Bit 5 **MIN**: Message init
1 = An acknowledgment was received from the Slave for the initialization of a message.
0 = No acknowledgment for the initialization received.
When this warning is displayed, the Parameters Channel is still in the initialization status and no "short message" or "long message" can be triggered.
This bit is level sensitive.

Bit 4 **ANS**: Erroneous answer to "long message"
1 = An error occurred during the answer to a long message. The effectiveness of the previous transaction is not known.
0 = The last answers to "long messages" were error free.
This error indicates that the transmission of an answer from the DSL Slave to the last "long message" failed. The frequency inverter application must send the "long message" again.

Bit 3 **Not implemented**: Read as "0".

Bit 2 **RET**: Fresh attempt at a "long" or "short" message
1 = Due to a transmission error, the answer to the "long message" or "short message" was requested again.
0 = The transmission of the answer to the "long message" or "short message" was error free.
This warning indicates that the transmission of a request to the DSL Slave, or the answer from the DSL Slave to the last "long message" or "short message" failed and will be attempted again automatically. If this warning occurs, the wiring of the DSL connection should be checked. If this warning is indicated continuously, there is probably an error in the motor feedback system.

Bit 1 **FREL**: Channel free for "long message"
1 = A "long message" can be sent on the Parameters Channel.
0 = No "long message" can be sent.
If the bit is set, the frequency inverter application can trigger a "long message". Provided no answer has been received from the DSL Slave, this bit remains deleted. As the processing duration of a "long message" in the motor feedback system is not specified, a user time limit condition should be installed via the frequency inverter application. When a time limit is exceeded, the **MRST** bit in the **SYS_CTRL** register is set, which causes the Parameters Channel to be reset.

Bit 0 **FRES**: Channel free for "short message"
1 = A "short message" can be sent on the Parameters Channel.
0 = No "short message" can be sent.
If the bit is set, the frequency inverter application can trigger a "short message". Provided no answer has been received from the DSL Slave, this bit remains deleted. As the processing duration of a "long message" in the motor feedback system is not specified, a time limit condition is installed in the DSL Master. If the time limit is exceeded, attempts are made again automatically (see under **RET** bit).

5.3.5. Event mask

In the event mask registers `MASK_H/MASK_L`, the events are set with which the `interrupt` signal is set.

Several events can be masked to trigger an interrupt. In addition, events from the DSL Slave summary can be combined with these events (see section 5.3.6). This is explained in Figure 20.

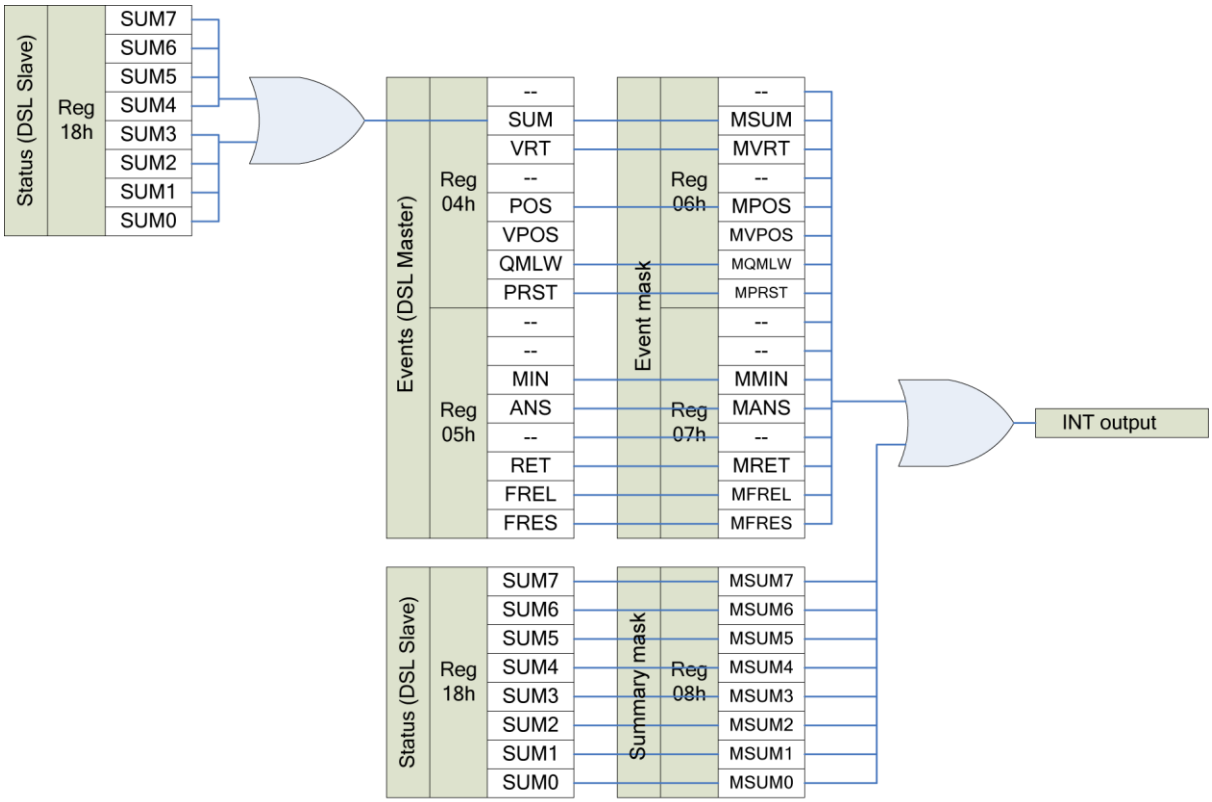


Figure 20: Interrupt masking

It should be noted that the **SUM** bit is an OR connection of all bits of the status summary (`SUMMARY` register).

Register 06h: **High Byte event mask**

X-0	W-0	W-0	X-0	W-0	W-0	W-0	W-0
	MSUM	MVRT		MPOS	MVPOS	MQMLW	MPRST
Bit 7							Bit 0

Bit 7 **Not implemented**: Read as "0".

Bit 6 **MSUM**: Mask for remote event monitoring
1 = DSL Slave events that are masked in the `SUMMARY` register set the `interrupt` signal.
0 = DSL Slave events that are masked in the `SUMMARY` register do not set the `interrupt` signal.

Bit 5 **MVRT**: Mask for transmission errors on the Safe Channel
1 = A transmission error on the Safe Channel sets the `interrupt` signal.
0 = A transmission error on the Safe Channel does not set the `interrupt` signal.

Bit 4 **Not implemented**: Read as "0".

Bit 3 **MPOS**: Mask for fast position error
1 = An error in the fast position sets the `interrupt` signal.
0 = An error in the fast position does not set the `interrupt` signal.

Bit 3 **MVPOS**: Mask for safe position error
1 = An error in the safe position sets the `interrupt` signal.
0 = An error in the safe position does not set the `interrupt` signal.

Bit 1 **MQMLW**: Mask for low quality monitoring value warning
1 = A low quality monitoring value (see registers 03h and 05h) sets the `interrupt` signal.
0 = A low quality monitoring value does not set the `interrupt` signal.

Bit 0 **MPRST**: Mask for protocol reset warning
1 = A protocol reset sets the `interrupt` signal.
0 = A protocol reset does not set the `interrupt` signal.

Register 07h: **Low Byte event mask**

X-0	X-0	W-0	W-0	X-0	W-0	W-0	W-0
		MMIN	MANS		MRET	MFREL	MFRES
Bit 7							Bit 0

Bit 7-6 **Not implemented**: Read as "0".

Bit 5 **MMIN**: Mask for message initialization confirmation
1 = The acknowledgment for the initialization of a DSL Slave message sets the `interrupt` signal.
0 = The acknowledgment for the initialization of a DSL Slave message does not set the `interrupt` signal.

Bit 4 **MANS**: Mask for erroneous answer to long message
1 = A transmission error during the answer to a long message sets the `interrupt` signal.
0 = A transmission error during the answer to a long message does not set the `interrupt` signal.

Bit 3 **Not implemented**: Read as "0".

Bit 2 **MRET**: Mask for a fresh attempt at a "long" or "short" message
1 = The fresh request for a "long message" or "short message" sets the `interrupt` signal.
0 = The fresh request for a "long message" or "short message" does not set the `interrupt` signal.

Bit 1 **MFREL**: Mask for "channel free for "long message"'
1 = If a "long message" can be sent on the Parameters Channel, the `interrupt` signal is set.
0 = If a "long message" can be sent on the Parameters Channel, the `interrupt` signal is not set.

Bit 0 **MFRES**: Mask for "channel free for "short message"'
1 = If a "short message" can be sent on the Parameters Channel, the `interrupt` signal is set.
0 = If a "short message" can be sent on the Parameters Channel, the `interrupt` signal is not set.

5.3.6. Summary mask

In the `MASK_SUM` summary mask register, the DSL Slave collective events are determined with which the **SUM** event monitoring in the event register as well as the signal to the interrupt pin are set (`interrupt`).

Several events can be masked to trigger an interrupt. In addition, events from the DSL Master can be combined with these events (see section 5.3.4).

It should be noted that the **MSUM** bit from the `MASK_H` register is an OR connection of all bits of the summary mask register.

Register 08h: **Summary mask**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-0
MSUM7	MSUM6	MSUM5	MSUM4	MSUM3	MSUM2	MSUM1	MSUM0
Bit 7							Bit 0

Bit 7-0 **MSUM7:MSUM0**: Mask for status summary bits
1 = In the set status, the corresponding status summary bit sets the **SUM** event monitoring and the signal at the `interrupt` pin.
0 = In the set status, the corresponding status summary bit does not set the **SUM** event monitoring and the signal at the `interrupt` pin.

5.3.7. Edges

The `EDGES` edge register contains the time control for the DSL cable bit sampling and can be used to monitor the connection quality.

Each individual edge register bit is set if, at system start-up, an edge of the test signal is detected during the time period of the corresponding bit. An edge is defined as a change in cable value between successive detections. The sampling is carried out eight times as fast as the cable bit rate.

Clean cable signals mean that only a few bits are set in the edge register, whilst noisy cable signals set a large number of bits.

CAUTION

If all bits in the edge register are set, this is an indication of excessive interference in the cable in which no connection can be established.

The register is write protected. The content of this register does not change after the start-up phase. A new bit sampling pattern is only generated after a forced reset of the protocol.

Register 09h: **Edges**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Bit sampling pattern							
Bit 7							Bit 0

Bit 7-0 **Bit sampling pattern**: Identification of edges in the cable signal
1 = An edge was detected in the time period of the corresponding bit.
0 = No edge was detected in the time period of the corresponding bit.

5.3.8. Delay

The DELAY run time register stores information about the run time delay of the system cable and the signal strength. The register can be used to monitor the connection quality.

The register is write protected.

Register 0Ah: **Run time delay**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
RSSI				Cable delay			
Bit 7							Bit 0

Bit 7-4 **RSSI**: Indication of the received signal strength
4 bit value for the cable signal strength, from "0" to "12". Higher values indicate better connection quality. If the value is less than "1" a forced reset of the protocol is carried out.

RSSI is continuously updated during operation and used for signal monitoring during run time.

Bit 3-0 **Cable delay**:
4 bit value for cable delay. This value gives the cable signal round trip delay of cable and transceivers in bits. This value enables a rough estimate of cable length to be made.

The value for **Line Delay** does not change after the start-up phase. A fresh value for **Line Delay** is only measured after a forced reset of the protocol.

Table 24 below shows the relationship between the value in **Line Delay** and the cable length of the DSL connection.

Cable delay	DSL connection cable delay	Cable length DSL connection
0	<100 ns	< 10 m
1	100 to 200 ns	10 to 20 m
2	200 to 300 ns	20 to 30 m
3	300 to 400 ns	30 to 40 m
4	400 to 500 ns	40 to 50 m
5	500 to 600 ns	50 to 60 m
6	600 to 700 ns	60 to 70 m
7	700 to 800 ns	70 to 80 m
8	800 to 900 ns	80 to 90 m
9	900 to 1000 ns	90 to 100 m

Table 24: Cable delay

A value above "9" indicates a delay of greater than 1 µs. Such a value will lead to a violation of the specification for cycle time. In this case, a check should be made of whether the cable complies with the cable specification.

5.3.9. Version

The VERSION version register contains the release version of the DSL Master IP Core.

The register is write protected.

Register 0Bh: **Version**

R-0	R-1	R-0	R-1	R-0	R-1	R-0	R-0
Coding		Major Release		Minor Release			
Bit 7							Bit 0

Bit 7-6 **Coding**: Type of IP Core
01= DSL Master IP Core

Bit 5-4 **IP Core Major release number**:
The current version is 1 (01).

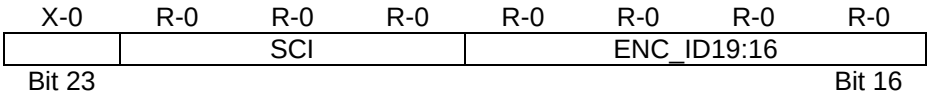
Bit 3-0 **IP Core Minor release number**:
The current version is 5 (0101).

5.3.10. Encoder ID

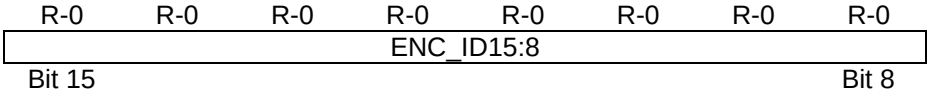
The ENC_ID encoder ID registers contain the designation code of the motor feedback system connected to the DSL Master. In the current protocol specification, the designation code is 20 bits long. With later enhancements, the free bits in the encoder ID registers are used to indicate special characters.

These registers are write protected.

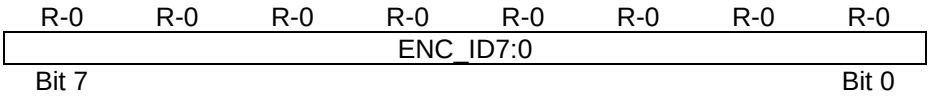
Register 0Dh: **Encoder ID, byte 2**



Register 0Eh: **Encoder ID, byte 1**



Register 0Fh: **Encoder ID, byte 0**



Bit 23 **Not implemented**: Read as "0".

Bit 22-20 **SCI**: Indication of special characters
3 bit special character for later enhancements of the encoder designation code. Not allocated.

Bit 19-0 **ENC_ID**: Encoder designation code
Designation of the motor feedback system (length: 20 bits)

The individual **ENC_ID** register bits are allocated as follows:

Bit 19 **Continue**: In High status, **Continue** indicates that ENC_ID is longer than 20 bits (for future use).

Bit 18 to 16 **Reserved**: Read as "0".

Bit 15 to 12 **User defined encoder index**: 4 bit value (0 to 15) for user-defined encoder index (see section 7.2.4.7).

Bit 11 **Reserved**: Read as "0".

Bit 10 **Sign**: In High status, **Sign** indicates that the position value is signed, in Low status, **Sign** indicates that the position value is not signed.

Bit 9 to 4 **#Pos-#Acc**: Length of position information (standard value: 40 bits) minus length of the acceleration value transmitted (, see section 5.3.11, standard value: 11 bits).

Bit 3 to 0 **#Acc-8**: Length of the acceleration value transmitted (, standard value: 11 bits) minus 8.

5.3.11. Fast position

The POS registers for the fast position contain the value of the motor feedback system connected. This position is generated incrementally from the safe position at start-up and is updated with every protocol frame.

After every eight protocol frames, the fast position is checked against the safe position (see under registers 18h to 1Ch).

The position sampling point is determined by the **ES** value of the synchronization control register.

Only those POS bits are activated that lie within the range that the motor feedback system has actually measured. All other higher value bits are read as "0". The number of measurable bits can be taken from **ENC_ID** bits 9 to 0 in the ENC_ID0 to 2 registers.

If **Sign** is set in the **ENC_ID** register, the value of the fast position is given signed in the two's complement.

The units of the position value are (steps).

These registers are write protected.

Register 10h: **Fast position, byte 4**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Fast position, byte 4							
Bit 39							Bit 32

Register 11h: **Fast position, byte 3**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Fast position, byte 3							
Bit 31							Bit 24

Register 12h: **Fast position, byte 2**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Fast position, byte 2							
Bit 23							Bit 16

Register 13h: **Fast position, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Fast position, byte 1							
Bit 15							Bit 8

Register 14h: **Fast position, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Fast position, byte 0							
Bit 7							Bit 0

Bit 39-0 **Fast position, byte 4/3/2/1/0**:
Position value of the motor feedback system (length: 40 bits), incrementally generated.

5.3.12. Speed

The VEL speed registers contain the speed values of the connected motor feedback system. This value is calculated as a Δ position from the acceleration value (ΔΔ position) transmitted on the process data channel and the currently updated protocol frame (see section 2).

The speed sampling point is determined by the **ES** value of the SYNC_CTRL register.

The units of the speed value are (steps/frame cycle time).

These registers are write protected.

Register 15h: **Speed, byte 2**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Speed, byte 2							
Bit 23							Bit 16

Register 16h: **Speed, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Speed, byte 1							
Bit 15							Bit 8

Register 17h: **Speed, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Speed, byte 0							
Bit 7							Bit 0

Bit 23-0 **Speed, byte 2/1/0**:
Speed of the motor feedback system (length: 24 bits)

5.3.13. Status summary

The SUMMARY status summary register contains the summarized DSL Slave status information. Each status summary bit contains the summarized information from 8 error, warning and event modes of the DSL Slave. The bits in the status summary register can be read and, if set, deleted. Figure 21 shows the relationship between the encoder status registers, the status summary register and the **SUM** bit in the EVENT registers.

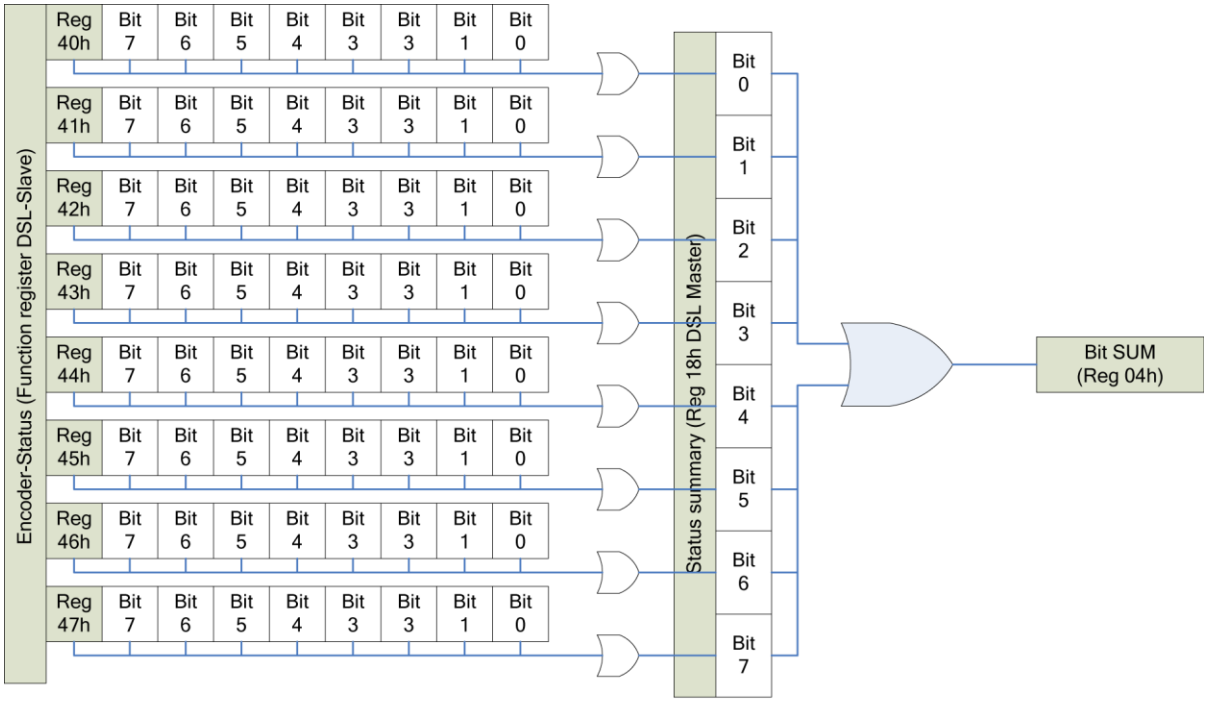


Figure 21: DSL Slave status and summary

A bit that has been set in the SUMMARY register is not automatically deleted by the DSL System. To delete, the frequency inverter application must read the corresponding DSL Slave encoder status register (see section 5.5.1) and acknowledge the status message, by individually deleting each set bit.

Register 18h: **Status summary**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
SUM7	SUM6	SUM5	SUM4	SUM3	SUM2	SUM1	SUM0
Bit 7							Bit 0

Bit 7-1 **SUM7:SUM1**: Status summary bit (external resource)
1 = An error, a warning or an event associated with DSL Slave external resources was triggered.
0 = The corresponding error, warning or event is not active.

Bit 0 **SUM0**: Status summary bit (interface)
1 = An error, a warning or an event associated with the DSL Slave protocol interface was triggered.
0 = The DSL Slave protocol has not triggered an error, warning or event.

5.3.14. Safe position

The VPOS registers for the safe position contain the position value from the primary channel of the motor feedback system connected. This safe position is transmitted in every eighth protocol frame if the validity of the data transfer has been checked.

The value for each safe position transmitted is compared with the incrementally generated position value (fast position) (see registers 10h to 14h).

The safe position is not synchronized with the sync signal.

Only those vpos bits are activated that lie within the range that the motor feedback system has actually measured. All other higher value bits are read as "0". The number of measurable bits can be taken from **ENC_ID** bits 9 to 0 in the ENC_ID0 to 2 registers.

If **Sign** is set in the **ENC_ID** register, the value of the safe position is given signed in the two's complement.

The units of the position value are [steps].

These registers are write protected.

Register 19h: **Safe position, byte 4**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, byte 4							
Bit 39							Bit 32

Register 1Ah: **Safe position, byte 3**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, byte 3							
Bit 31							Bit 24

Register 1Bh: **Safe position, byte 2**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, byte 2							
Bit 23							Bit 16

Register 1Ch: **Safe position, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, byte 1							
Bit 15							Bit 8

Register 1Dh: **Safe position, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, byte 0							
Bit 7							Bit 0

Bit 39-0 **Safe position, byte 4/3/2/1/0**:
Position value at motor feedback system Channel 1 (length: 40 bits), absolute value transmitted.

5.3.15. Position checksum

The POSCRC registers for the position checksum contain the CRC checksum of the safe position VPOS (see section 5.3.14) and the SUMMARY status summary (see section 5.3.13).

The CRC is checked in the DSL Master IP Core. In order to guarantee, in a safety related application, that the CRC machine in the IP Core is functioning, these registers can be checked with an external cross check in the diagnostics test interval. This interval is described in the section about safety implementation (see the HIPERFACE DSL® safety implementation manual).

The CRC is generated with the following CRC parameters:

Parameter	Value
CRC sequence	16 Bit
CRC polynomial	C86Ch ($x^{16} + x^{15} + x^{12} + x^7 + x^6 + x^4 + x^3 + 1$)
Starting value	0000h
Closing XOR value	00FFh
Reverse data bytes	No
Reverse CRC before closing XOR	No

Table 25: POSCRC parameters

The sequence of the bytes to calculate the CRC is shown in the following figure:

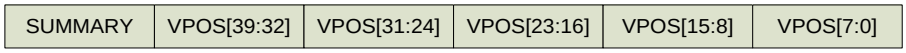


Figure 22: Sequence of the bytes to calculate the CRC

Register 1Eh: **CRC of the safe position, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
CRC of the safe position, byte 1							
Bit 15							Bit 8

Register 1Fh: **CRC of the safe position, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
CRC of the safe position, byte 0							
Bit 7							Bit 0

Bit 15-0 **CRC of the safe position**:
16 bit CRC checksum (CRC 16) of the safe position and status summary in Channel 1.

5.3.16. Parameters Channel buffer

The eight PC_BUFFER registers of the Parameters Channel buffer contain the answer to the last "long message" request or the data for a "long message" write operation.

Access to these registers may only take place if the "long message" channel is free (**FREL** in the EVENT_L register).

Depending on the length of the "long message" answer, the registers are used as follows:

Length of the "long message"	Register used
8 bytes	20h to 27h
4 bytes	20h to 23h
2 bytes	20h to 21h
0 bytes	None

Table 26: Data length of the "long message"

These registers are also for the reporting of error conditions arising from a "long message" operation. If, when accessing a resource, an error due to a "long message" arises (e.g. invalid data, error in the A/D conversion, time overrun), after the answering message has been received the **LOFF** bit in the PC_ADD_H register (28h) is set. In this case the Parameters Channel buffer bytes 0 and 1 contain an error code.

The meaning of the error code depends on the particular HIPERFACE DSL® encoder and is described in detail in the data sheet.

Register 20h: **Parameters Channel buffer, byte 0**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 0							
Bit 63							Bit 56

Register 21h: **Parameters Channel buffer, byte 1**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 1							
Bit 55							Bit 48

Register 22h: **Parameters Channel buffer, byte 2**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 2							
Bit 47							Bit 40

Register 23h: **Parameters Channel buffer, byte 3**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 3							
Bit 39							Bit 32

Register 24h: **Parameters Channel buffer, byte 4**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 4							
Bit 31							Bit 24

Register 25h: **Parameters Channel buffer, byte 5**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 5							
Bit 23							Bit 16

Register 26h: **Parameters Channel buffer, byte 6**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 6							
Bit 15							Bit 8

Register 27h: **Parameters Channel buffer, byte 7**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Parameters Channel, byte 7							
Bit 7							Bit 0

Bit 63-0 **Parameters Channel buffer, byte 0-7**:
8 bytes for the answer to a long message (read operation) or for a "long message" write operation.

Bit 63-48 **Error report for a long message, byte 0-1**:
2 bytes for reports about errors in encoder resources arising from the previous "long message" operation.

5.3.17. Long message address

The addresses and the addressing mode for "long messages" sent over the Parameters Channel are determined in the PC_ADD_H/PC_ADD_L long message address registers.

In addition, the long message address register 28h (PC_ADD_H) contains indications of errors arising from "long message" operations. For this sort of error, the Parameters Channel buffer contains the error code in bytes 0 and 1 associated with this status (see section 6.7.5).

Register 28h: **Long message address, byte 1**

R-1	W-0	R/W-0	W-0	W-0	W-0	W-0	W-0
LID	LRW	LOFF	LIND	LLEN		LADD9	LADD8
Bit 15							Bit 8

Register 29h: **Long message address, byte 0**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-0
LADD7:0							
Bit 7							Bit 0

Bit 15 **LID**: Long message identification. The value must be "1".

Bit 14 **LRW**: Long message, read/write mode
1 = "long message" read operation
0 = "Long message" write operation

Bit 13 **LOFF**: Long message addressing mode/long message error
Write access:
1 = Offset addressing of "long messages". The offset value from the PC_OFF_H/PC_OFF_L registers is used in the resource of the selected database entry as a sub-address.
0 = Addressing of "long messages" without offset. The offset value from the PC_OFF_H/PC_OFF_L registers is not used.

Read access:
1 = The last "long message" caused an error.
0 = The last "long message" was correctly processed.

Bit 12 **LIND**: Indirect addressing of long messages
1 = Indirect addressing of "long messages". During this operation, the stored address content in the given database entry is evaluated.
0 = Direct addressing of "long messages". The operation affects the database entry given in the current address.

Bit 11-10 **LLEN**: Data length of the "long message"
11 = 8 data bytes
10 = 4 data bytes
01 = 2 data bytes
00 = No data bytes

Bit 9-0 **LADD**: Long message address
Database entry with 10 bit address for a "long message" operation.

5.3.18. Long message address offset

The PC_OFF_H/PC_OFF_L address offset registers for long messages are used in "long message" operations, if **LOFF** is set in the register 28h. In this case the LOFFADD value from these registers is used to communicate with the sub-address of a multiple byte encoder resource.

Only write access is possible for these registers.

Register 2Ah: **Long message address offset, byte 1**

R-1	W-0	W-0	W-0	W-0	W-0	W-0	W-0
LID	LOFFADD14:8						
Bit 15							Bit 8

Register 2Bh: **Long message address offset, byte 0**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-0
LOFFADD7:0							
Bit 7							Bit 0

Bit 15 **LID**: Long message identification. The value must be "1".

Bit 14-0 **LOFFADD14:0**: Long message offset value
The 15 bit offset value of the "long message" address offset is stored in these bits.

5.3.19. Parameters Channel control

The PC_CTRL control register for the Parameters Channel handles the start of "long message" transactions. After setting all "long message" registers (registers PC_BUFFER0 to 7, PC_ADD_H/PC_ADD_L and PC_OFF_H/L), the "long message" is transmitted to the DSL Slave by setting the **LSTA** bit.

Register 2Ch: **Parameters Channel control**

X-0	X-0	X-0	X-0	X-0	X-0	X-0	W-0
							LSTA
Bit 7							Bit 0

Bit 7-1 **Not implemented**: Read as "0".

Bit 0 **LSTA**: Control of the long message start
1 = A "long message" transaction is started with the values currently stored in the "long message" registers.
0 = No effect.

5.3.20. SensorHub Channel status

The SensorHub Channel status register PIPE_S provides information about the current status of the SensorHub Channel (see section 2.5. SensorHub Channel).

PIPE_S is only accessible as a register of the DSL Master if SPI-PIPE is deactivated (**SPPE** in the SYS_CTRL register is deleted).

Otherwise the value of PIPE_S is transmitted via SPI-PIPE as the first byte of each read request (see section 4.3). In this case, the first four bits are transmitted as "0101" to check the SPI-PIPE interface for errors due to unchanged values.

When this register is read, the current data from the FIFO buffer is read and stored in an intermediate register so that a subsequent read process in the PIPE_D register can be considered to be completed at the same time as the PIPE_S register is read. Using this mechanism, any deviation between status and data information in this instance will prevent new data entering the SensorHub Channel during access to the FIFO buffer.

PIPE_S is a write protected register.

Register 2Dh: **SensorHub Channel status**

X-0	X-0	X-0	X-0	R-0	R-0	R-0	R-0
				POVR	PEMP	PERR	PSCI
Bit 7							Bit 0

Bit 7-4 **Not implemented**: Read as "0".

Bit 3 **POVR**: SensorHub Channel overflow
1 = The capacity of the 8 byte FIFO buffer for SensorHub Channel data was exhausted and since the last read process, values have been discarded.
0 = The capacity of the FIFO buffer for SensorHub Channel data is not yet exhausted.
This bit is deleted after the read process.

Bit 2 **PEMP**: The SensorHub channel buffer is empty.
1 = A read request was issued, but the FIFO buffer for SensorHub Channel data is empty. In this case, PIPE_D contains the value 00h.
0 = No "buffer empty" error.
This bit is updated after every access to the FIFO buffer.

Bit 1 **PERR**: Coding error of the bits in the SensorHub Channel.
1 = The bit level coding of the data currently in the SensorHub Channel is erroneous.
0 = No error in bit coding.
This bit is stored together with the pipeline data byte in question in the FIFO buffer.

Bit 0 **PSCI**: Indication for special characters in the SensorHub Channel.
1 = A special character was received in the SensorHub Channel.
0 = Indication for "no special character".
This bit is stored together with the pipeline data byte in question in the FIFO buffer.

Special characters are normally used as data separators or to indicate special events. To obtain information about which special character was received, the PIPE_D register must be read. All 8b10b special characters can be used on the SensorHub channel. An exception is the "K30.7" symbol that is used in HIPERFACE DSL® to indicate "no data" and is not stored in the FIFO buffer.

Table 27 below contains the supported 8b10b special characters.

Special characters	**Coding in register** PIPE_D
K28.0	1Ch
K28.1	3Ch
K28.2	5Ch
K28.3	7Ch
K28.4	9Ch
K28.5	BCh
K28.6	DCh
K28.7	FCh
K23.7	F7h
K27.7	FBh
K29.7	FDh

Table 27: 8b10b special characters supported in the SensorHub Channel

5.3.21. SensorHub Channel data

The PIPE_D SensorHub Channel data register contains the SensorHub Channel data that is stored in an 8 byte FIFO buffer.

If new data arrives at the buffer when it is full, before PIPE_D is read, the oldest value is discarded and the **POVR** bit in PIPE_S is set.

If a read request is issued when the buffer is empty, the **PEMP** bit inPIPE_S is set and the value 00h is transmitted.

PIPE_D is only accessible as a register of the DSL Master if SPI-PIPE is deactivated (**SPPE** in the SYS_CTRL register is deleted).

Otherwise the value of PIPE_D is transmitted via SPI-PIPE as the second byte of each read request (see section 4.3).

At the moment that the PIPE_S register is accessed, the corresponding PIPE_D value is frozen to guarantee synchronization between status and data information.

PIPE_D is a write protected register.

Register 2Eh: **Sensor Hub Channel data**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
SensorHub Channel data							
Bit 7							Bit 0

Bit 7-0 **SensorHub Channel data**
8 bit value of the FIFO buffer for SensorHub Channel data.

5.3.22. Parameters Channel short message

The PC_DATA register for the Parameters Channel short message contains the results of "short message" transactions.

"Short message" transactions are generated if operations are carried out with remote registers (DSL Slave). Generally, **FRES** (in the EVENT_L register) must be set after a transaction is started. Only then will PC_DATA contain valid information.

Register 2Fh: "**Short message" Parameters Channel data**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
"Short message" Parameters Channel data							
Bit 7							Bit 0

Bit 7-0 **"Short message" Parameters Channel data**
8 bit value of the requested remote register.

5.3.23. Fast position error counter

The ACC_ERR_CNT register returns the count of transmitted fast position values with consecutive transmission errors. The value is clamped to a maximum of 31 (1Fh).

With a writing access the error threshold for the test signal acc_thr_err can be set. This value is also clamped to a maximum of 31 (1Fh). If the count of transmitted fast position values with consecutive transmission errors exceeds this threshold acc_thr_err will be set to '1'.

Register 38h: **Fast position error counter**

X-0	X-0	X-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
-	-	-	CNT4	CNT3	CNT2	CNT1	CNT0
Bit 7							Bit 0

Bit 7-5 **Not implemented**: Read as "0".

Bit 4-0 **CNT4:CNT0**: Position error count/threshold for acc_thr_err
Read: 5 bit value of count of transmitted fast position values with consecutive transmission errors
Write: 5 bit value for threshold of acc_thr_err

5.3.24. Fast position acceleration boundary

The MAXACC register allows setting an acceleration threshold for a given application. This threshold is used by the fast position estimator to clamp the acceleration of the estimated position during communication or sensor failures of the fast position channel.

The narrower the acceleration boundaries are set, the longer the position estimator can provide for good estimations of the true position during fault conditions.

All actual contributions to application should be taken into account for this setting (for instance gravity) and not only the foreseen application kinematics. Some margin should also be given to the maximum limit in order to account for noise, inaccuracy and so on.

The maximum absolute value of the acceleration must be written to the MAXACC register in a floating point format. The exponent is stored in bits 7 and 6, and a positive integer mantissa on the remaining part of the register. The resulting value can be calculated as follows:

$$\left|acc_{\max}\right| = mantissa \cdot resolution$$

Here, *mantissa* is the value stored in bits 5…0 and resolution is defined as per the following table:

Bit 7,6	Resolution
00	ACC_{LSB} / 256
01	ACC_{LSB} / 64
10	ACC_{LSB} / 16
11	ACC_{LSB} / 4

Table 28: Resolution of fast position acceleration boundary

The ACC_{LSB} value is the resolution of the DSL fast position channel which can be calculated as:

$$ACC_{LSB} = \frac{2\pi}{2^{Pres} \cdot T_{hframe}^2} [rad/s^2]$$

with Pres as position resolution per turn in number of bits and T_{hframe} as DSL frame duration in s (see ch. 2)

Example:

If the DSL frame lasts 15.625µs, an 18 bit resolution encoder is used, and a limit of 10000 rad/s² is foreseen:

$$ACC_{LSB} = \frac{2\pi}{2^{18} \cdot \left(15.625 \cdot 10^{-6}\right)^2} = 98174.77\ rad/s^2$$

The finest possible resolution for acc_{max} is $ACC_{LSB}/256$ = 383.5 *rad/s²*. Accordingly, acc_{max} can be set to

$$acc_{max} = 27 \cdot 383.5\ rad/s^2 = 10355\ \ rad/s^2$$

with a setting of 0x1B in the MAXACC register.

Values greater than 24000 *rad/s²* can be achieved by using different resolutions: on the same system as above, a limit of 30000 *rad/s²* can be set using $ACC_{LSB}/64$ = 1534 *rad/s²*.

Therefore:

$$acc_{max} = 20 \cdot 1534\ \ rad/s^2 = 30680\ \ rad/s^2$$

In this case the data to be written to the MAXACC register would be 0x54.

It should be noted that the position estimator only provides for the fast position channel and not for either of the two safe channels.

Register 39h: **Fast position acceleration boundary**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-0
RES1	RES0	MNT5	MNT4	MNT3	MNT2	MNT1	MNT0
Bit 7							Bit 0

Bit 7-6 **RES1:RES0**: Resolution of fast position acceleration boundary

Bit 5-0 **MNT5:MNT0**: Mantissa of fast position acceleration boundary

5.3.25. Fast position estimator deviation

The MAXDEV registers return the maximum absolute position deviation while the position estimator is active. The returned 16 bit value has the same format (resolution) as the fast position channel and is clamped to a maximum of 65535 steps (0xFFFF). The registers are set to the maximum value 0xFFFF at reset.

These registers also allow setting a deviation threshold value for triggering the output signal maxdev (see ch. 4.4.7). The threshold value can be written with the same format as the deviation (unsigned 16 bit, same resolution as the fast position channel).

Register 3Ah: **Fast position estimator deviation high byte**

R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1
DEV15	DEV14	DEV13	DEV12	DEV11	DEV10	DEV09	DEV08
Bit 15							Bit 8

Register 3Bh: **Fast position estimator deviation low byte**

R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1	R/W-1
DEV07	DEV06	DEV05	DEV04	DEV03	DEV02	DEV01	DEV00
Bit 7							Bit 0

Bit 15-0 **DEV15:DEV00**: Position deviation/Deviation threshold
Read: 16 bit value of position deviation
Write: 16 bit value for deviation threshold for maxdev

5.4. DSL Master function register on Channel 2

The registers in the DSL Master IP Core on Channel 2 are used for protocol logic access to Channel 2 position values. Table 29 contains a list of these registers on Channel 2.

Addr	Designation	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Value at reset
0Fh	ENC2_ID	ENC2_ID7:0								0000 0000
18h	VPOS24	Safe position, Channel 2, byte 4								0000 0000
19h	VPOS23	Safe position, Channel 2, byte 3								0000 0000
1Ah	VPOS22	Safe position, Channel 2, byte 2								0000 0000
1Bh	VPOS21	Safe position, Channel 2, byte 1								0000 0000
1Ch	VPOS20	Safe position, Channel 2, byte 0								0000 0000
1Dh	VPOSCRC2_H	Safe position, CRC 2, byte 1								0000 0000
1Eh	VPOSCRC2_L	Safe position, CRC 2, byte 0								0000 0000
1Fh	STATUS2	Status Channel 2								0000 0000
3Fh	DUMMY2	No data								---- ----

Table 29: Description of the registers in DSL Master, Channel 2

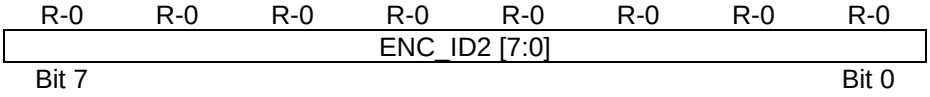
5.4.1. Encoder ID in Channel 2

The ENC2_ID register for the ID of the encoder in Channel 2 contains the designation code for the secondary channel of the DSL encoder.

The contents of ENC2_ID are defined during the actual installation of the motor feedback system and can be found in the corresponding data sheet.

The register is write protected.

Register 0fh: **Encoder ID in Channel 2**



Bit 7-0 **ENC_ID2**: Designation of the secondary channel
02h: SIL2 arrangement. The same position data is transmitted to the secondary channel as to the primary channel.
03h: SIL3 arrangement. Position data is transmitted to the secondary channel that originates from the secondary sensor in the HIPERFACE DSL® motor feedback system.

5.4.2. Channel 2 status

The STATUS2 status register for Channel 2 contains the status information for Channel 2 of the HIPERFACE DSL® motor feedback system. A summary of the contents is also available in the SP12 Online Status (see section 5.2.2).

It should be noted that the bits in STATUS2 do not maintain their status and therefore perform differently than the bits in the Channel 1 status summary (see section 5.3.13). It is therefore not necessary (and not possible) to acknowledge the status of the bits in STATUS2.

CAUTION

All fault indications in the STATUS2 register are potentially critical and safety-related. Suitable measures must be installed in the user application.

Register 18h: **Status of Channel 2**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
TOG2	TEST2	ERR2	FIX2				
Bit 7							Bit 0

Bit 7 **TOG2**: Channel 2 toggle bit
For successive position transmissions on Channel 2, **TOG2** must always toggle between "0" and "1". The starting value for **TOG2** is "0". If the toggle bit does not change its value, it is probable that a transmission error occurred and the transmitted absolute value for Channel 2 is invalid. **Suitable measures must be installed in the user application.**

Bit 6 **TEST2**: Channel 2 has just been tested
TEST2 is set if a test is carried out during the currently available Channel 2 status and position values.

TEST2 can only be valid if the user application has previously requested a test (see section 5.5.3).

Corresponding error indications for **TEST2** are either the **ERR2** bit or a discrepancy between the position and the CRC of Channel 2.

The table below contains the possible scenarios and the corresponding responses from the user application.

Test requested on Channel 2	TEST2	ERR2	Position 2 and CRC 2 agree	Action from the user application
None	0	0	0	None
None	0	0	1	Appropriate error handling
None	0	1	0	Appropriate error handling
None	0	1	1	Appropriate error handling
None	1	Variable	Variable	Appropriate error handling
ERR2	0	0	0	Appropriate error handling following time overrun
ERR2	0	0	1	Appropriate error handling
ERR2	0	1	0	Appropriate error handling
ERR2	0	1	1	Appropriate error handling
ERR2	1	0	0	Appropriate error handling
ERR2	1	0	1	Appropriate error handling
ERR2	1	1	0	None
ERR2	1	1	1	Appropriate error handling
Pos/CRC2	0	0	0	Appropriate error handling following time overrun
Pos/CRC2	0	0	1	Appropriate error handling
Pos/CRC2	0	1	0	Appropriate error handling
Pos/CRC2	0	1	1	Appropriate error handling
Pos/CRC2	1	0	0	Appropriate error handling
Pos/CRC2	1	0	1	None
Pos/CRC2	1	1	0	Appropriate error handling
Pos/CRC2	1	1	1	Appropriate error handling

Table 30: Test carried out on Channel 2

Bit 5 **ERR2:** Channel 2, position error
1 = The last safe position received in Channel 2 is invalid. **Suitable measures must be installed in the user application.**
0 = The last safe position received on Channel 2 was correct.

Bit 4-0 **FIX2**: Channel 2, fixed bit pattern
FIX2 is a fixed bit pattern for each SPI2 transaction that indicates errors arising in the SPI2 interface due to unchanged bit values. The standard value of the fixed bit pattern is "11100". All other values indicate an error on Channel 2 of the DSL system. **Suitable measures must be installed in the user application.**

5.4.3. Safe position, Channel 2

The VPOS2 registers for the Channel 2 safe position contain the position value from the secondary channel of the motor feedback system connected. This safe position is transmitted in every eighth protocol frame if the validity of the data transfer has been checked.

The safe position is not synchronized with the SYNC signal.

Only those VPOS2 bits are activated that lie within the range that the motor feedback system has actually measured. All other higher value bits are read as "0". The number of measurable bits can be taken from **ENC2_ID** bits 9 to 0 in the ENC2_ID0 to 2 registers.

The VPOS2 position is given as a complementary value to VPOS from the safe position in Channel 1. If the motor feedback system in Channel 1 and 2 provides different resolutions, the position values only agree for the higher value bits.

The units of the position value are [steps].

These registers are write protected.

Register 19h: **Safe position, Channel 2, byte 4**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, Channel 2, byte 4							
Bit 39							Bit 32

Register 1Ah: **Safe position, Channel 2, byte 3**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, Channel 2, byte 3							
Bit 31							Bit 24

Register 1Bh: **Safe position, Channel 2, byte 2**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, Channel 2, byte 2							
Bit 23							Bit 16

Register 1Ch: **Safe position, Channel 2, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, Channel 2, byte 1							
Bit 15							Bit 8

Register 1Dh: **Safe position, Channel 2, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
Safe position, Channel 2, byte 0							
Bit 7							Bit 0

Bit 39-0 **Safe position, Channel 2, byte 4/3/2/1/0**:
Position value at motor feedback system Channel 2 (length: 40 bits), transmitted as an absolute value complement.

5.4.4. Checksum for the position in Channel 2

The POSCRC2 registers for the position checksum in Channel 2 contain the CRC checksum for the safe position VPOS2 (see section 5.4.3).

The CRC is checked in the DSL Master IP Core. In order to guarantee, in a safety related application, that the CRC machine in the IP Core is functioning, these registers can be checked with an external cross check in the diagnostics test interval. This interval is described in the section about safety implementation (see the HIPERFACE DSL® Safety Implementation Manual).

The CRC is generated with the following CRC parameters:

Parameter	Value
CRC sequence	16 Bit
CRC polynomial	C86Ch ($x^{16} + x^{15} + x^{12} + x^7 + x^6 + x^4 + x^3 + 1$)
Starting value	0000h
Closing XOR value	00FFh
Reverse data bytes	No
Reverse CRC before closing XOR	No

Table 31: POSCRC parameters

The sequence of the bytes to calculate the CRC is shown in the following figure:

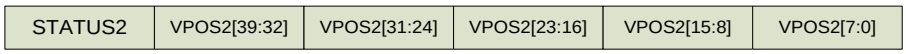


Figure 23: Sequence of the bytes to calculate the CRC

Register 1Eh: **CRC of the safe position, byte 1**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
CRC of the safe position 2, byte 1							
Bit 15							Bit 8

Register 1Fh: **CRC of the safe position, byte 0**

R-0	R-0	R-0	R-0	R-0	R-0	R-0	R-0
CRC of the safe position 2, byte 0							
Bit 7							Bit 0

Bit 15-0 **CRC of the safe position 2**:
16 bit CRC checksum (CRC 16) of the safe position and status summary in Channel 2.

5.5. Function register for the DSL Slave

The remote registers of the DSL Slave are mirrored in the DSL Master under the addresses 40h to 7Fh. These registers are accessible using "short message" transactions (see section 6.6.1).

It should be noted that the DSL Slave register can only be accessed via 8 bit addressing. If a 16 bit wide interface is used, the higher value byte will always be returned as "0". The `bigend` option does not affect the Slave register address allocation.

The minimum number of remote registers present in the DSL Slave is set out in Table 32. For real DSL Slave installations, more remote registers can be installed than are set out in the table.

Address	Designation	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Value at reset
40h	ENC_ST0	ST07	ST06	ST05	ST04	ST03	ST02	ST01	ST00	0000 0000
41h	ENC_ST1	ST17	ST16	ST15	ST14	ST13	ST12	ST11	ST10	0000 0000
42h	ENC_ST2	ST27	ST26	ST25	ST24	ST23	ST22	ST21	ST20	0000 0000
43h	ENC_ST3	ST37	ST36	ST35	ST34	ST33	ST32	ST31	ST30	0000 0000
44h	ENC_ST4	ST47	ST46	ST45	ST44	ST43	ST42	ST41	ST40	0000 0000
45h	ENC_ST5	ST57	ST56	ST55	ST54	ST53	ST52	ST51	ST50	0000 0000
46h	ENC_ST6	ST67	ST66	ST65	ST64	ST63	ST62	ST61	ST60	0000 0000
47h	ENC_ST7	ST77	ST76	ST75	ST74	ST73	ST72	ST71	ST70	0000 0000
7Ch	SRSSI	-	-	-	-	-	SRSSI2:0			---- -000
7Eh	MAIL	Slave-Mail								0000 0000
7Fh	PING	Slave-Ping [1]								0000 0000

Table 32: Remote slave register

5.5.1. Encoder status

The `ENC_ST` encoder status registers contain all slave system errors, events and warnings from Channel 1 of the DSL encoder.

The allocation between the individual bits and the slave system statuses is determined when the DSL Slave is installed and set out in the associated data sheet. The general application of the status register follows the list in Chapter 6.7.4.

It should be noted that all bits of an encoder status register are OR linked and mirror bits in the `SUMMARY` DSL Master register (1Fh) (see Table 33 and Figure 21 in section 5.3.13). In this way the appropriate groups can react rapidly to slave statuses.

Bits in the encoder status register can only be set by the DSL Slave and only deleted by the frequency inverter application (acknowledgment).

[1] After a protocol reset, the `PING` register contains the slave interface version (see section 5.5.4).

Encoder status	SUMMARY bit (DSL Master 1Fh)
ENC_ST0 (40h)	SUM0
ENC_ST1 (41h)	SUM1
ENC_ST2 (42h)	SUM2
ENC_ST3 (43h)	SUM3
ENC_ST4 (44h)	SUM4
ENC_ST5 (45h)	SUM5
ENC_ST6 (46h)	SUM6
ENC_ST7 (47h)	SUM7

Table 33: Encoder status and summary register

Register 40h: **Encoder status, byte 0**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 7							Bit 0

Register 41h: **Encoder status, byte 1**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 15							Bit 8

Register 42h: **Encoder status, byte 2**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 23							Bit 16

Register 43h: **Encoder status, byte 3**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 31							Bit 24

Register 44h: **Encoder status, byte 4**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 39							Bit 32

Register 45h: **Encoder status, byte 5**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 47							Bit 40

Register 46h: **Encoder status, byte 6**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 55							Bit 48

Register 47h: **Encoder status, byte 7**

R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0	R/C-0
Encoder status							
Bit 63							Bit 56

Bit 63-0 **Encoder status**
The individual bits indicate different errors, events and warnings. The meaning of each individual bit is determined by the particular DSL Slave installation. Generally the specification in section 6.7.4 applies.
1 = Error, event or warning status.
0 = Encoder in normal status.

5.5.2. Slave RSSI

The `SRSSI` register for indicating the received signal strength at the slave (Slave Received Signal Strength Indicator, RSSI) provides an indication of the strength of the signal arriving at the slave.

The value of the register is only updated from frame to frame if the measurement result deteriorates. After a read access to this register, the register is reset to the value "7" (maximum signal strength).

The register is write protected.

Register 7Ch: **Slave RSSI**

X-0	X-0	X-0	X-0	X-0	R-0	R-0	R-0
					SRSSI		
Bit 7							Bit 0

Bit 7-3 **Not implemented**: Read as "0".

Bit 2-0 **Value of the Slave RSSI**
The values for the Slave RSSI range from "0" (poorest signal strength) to "7" (best signal strength).

5.5.3. Slave-Mail

The MAIL multi-purpose register of the slave is used for fast communication with the DSL motor feedback system processor. The content of the slave mail register is transmitted to the encoder processor by the most rapid route possible.

In safety-related applications, the slave mail register is used for the transmission of test messages to the DSL motor feedback system. The correct use of the register in safety-related applications is described in the HIPERFACE DSL® Safety Implementation Manual.

This register is write protected.

Register 7Eh: **Slave Mail**

W-0	W-0	W-0	W-0	W-0	W-0	W-0	W-0
Slave-Mail							
Bit 7							Bit 0

Bit 7-0 **Slave-Mail**
8 bit slave mail data for multiple applications.

5.5.4. Slave-Ping

The PING register of the slave is used to carry out connection tests on behalf of the DSL Slave. The register can be written to and read externally, without this affecting the DSL interface.

On start-up, the register is initialized with the DSL Slave interface hardware version.

Register 7Fh: **Slave-Ping**

R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
Slave-Ping							
Bit 7							Bit 0

Bit 7-0 **Slave-Ping**
8 bit hardware version of the DSL encoder at start-up. This value is "0001 0001". On first reading, the Ping value of the slave can be used as a connection test on behalf of the slave.

6. Central functions

In this chapter, access to the central sensor functionality via interfaces and registers is described.

6.1. System start

As soon as the motor feedback system is supplied with power, a forced reset ensures that a defined system start status is produced in the DSL Master IP Core (see section 4.4.3).

Figure 24 shows the status table for system start.

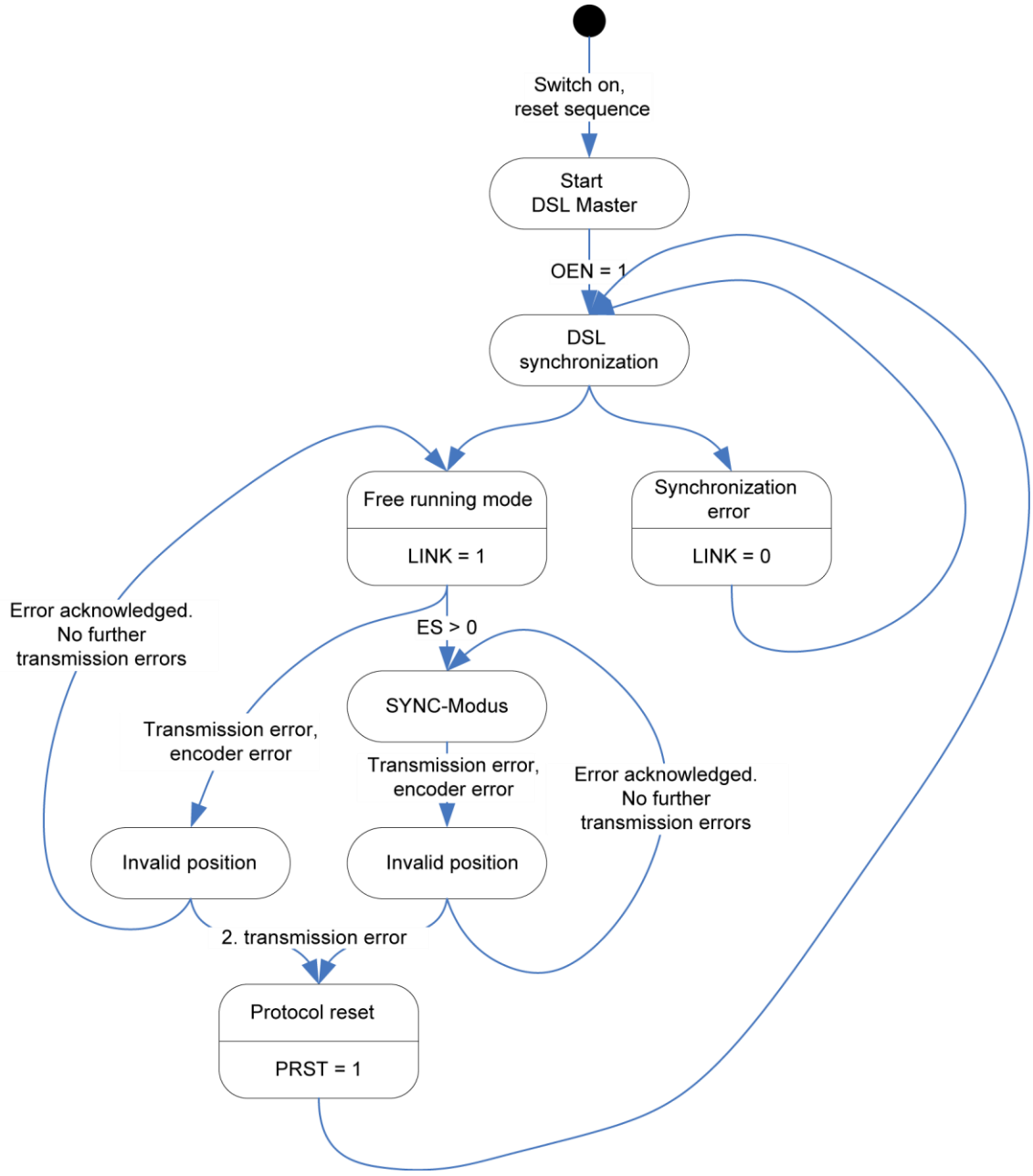


Figure 24: Status table for DSL system start.

Individual conditions are described in Table 34.

Status	Prerequisite	Indication
DSL Master start	Switching on supply voltage. Reset process (Duration: 500 msec)	Communication via Interface 1 or Interface 2 is possible
DSL synchronization	**OEN** = 1 (**SYS_CTRL** register)	None
Synchronization error	Time overrun during the DSL synchronization	**LINK** = 0 (**MASTER_QM** register)
Free running mode	Successful DSL synchronization	**LINK** = 1 (**MASTER_QM** register)
SYNC mode	**ES** > 0 (**SYNC_CTRL** register), Cyclic signal to SYNC input	Synchronous encoder position in the POS0 to POS4 registers
Invalid position	External transmission or encoder error	Error bit set in **EVENT_H**, **EVENT_L** or in Online Status 1
Protocol reset	Two successive transmission errors	**PRST** = 1 (**EVENT_H** register or Online Status)

Table 34: Conditions at DSL system start

6.2. System diagnostics

HIPERFACE DSL® provides comprehensive system diagnostics in relation to communications quality both during the development of a DSL system as well as during normal operation.

6.2.1. System diagnostics during development

During the development of a DSL system, several registers are involved in the diagnostics of correct use and operation. These include:

- Quality monitoring `MASTER_QM`
- Edge register `EDGES`
- Run time register `DELAY`

After the DSL connection has been activated (**OE** bit, see section 6.1), the **LINK** flag in the `MASTER_QM` register must be checked for the set value "1". This indicates that the connection to the motor feedback system was successfully established.

If this bit remains deleted for longer than the prescribed start-up time (see Table 8), there is a fundamental problem in the connection between the frequency inverter and the motor feedback system.

Check whether the encoder is supplied with power.

Using an oscilloscope, also check whether any level changes in the transmission frequency range can be identified over the data cables between the frequency inverter and the encoder (see Table 8).

Using the run time register (see section 5.3.8), it is possible to identify whether the DSL signal **cable delay** complies with the specification. The run time is mainly a result of the length of the cable between the frequency inverter and the motor feedback system. In addition, the selection of the interface drive (RS485 transceiver) has an effect on the signal run time.

The value of the EDGES register (see section 5.3.7) indicates how well or badly the DSL Master can sample the communication signal coming from the motor feedback system.

Start the check of the **bit sampling pattern** with the motor switched off. If several bits have been set in the sampling pattern (more than four), the encoder shielding design should be checked. The aim should be that, during interference-free operation, the minimum number of bits is set in the sampling pattern.

In the second step, check the sampling pattern with the motor switched on, preferably in the target application. In such cases a maximum of seven bits may be set in the EDGES register.

If under certain circumstances, however, eight bits are set in the EDGES register, the operation of the DSL motor feedback system cannot be guaranteed.

6.2.2. System diagnostics during operation

When operating the DSL system, system diagnostics are indicated in the following registers:

- Run time register DELAY
- Quality monitoring MASTER_QM
- Indication of the received signal strength at the SRSSI slave

The run time register (see section 5.3.8) contains the **RSSI** value that lies in the range between "0" and "12". The register indicates the quality of the connection during operation with regard to the signal strength.

The quality monitoring (see section 5.3.3) contains the **QM** value that lies in the range between "0" and "15". **QM** indicates the quality of the connection during operation with regard to transmission errors.

For continuous monitoring of the connection quality it is recommended that these two values are polled cyclically.

Event-oriented monitoring is also possible. For this, the event bits **QMLW** and **PRST** must be polled. These bits indicate **QM** sinking below a value of "14" (poor quality) or a broken connection if **QM** has a value of "0" or **RSSI** has a maximum value of "1". The following table contains the possible conditions:

Quality monitoring value	RSSI value	QMLW	PRST	Connection status	LINK	
15	12 to 2	0	0	Good connection quality	1	
14 to 1		1	0	Poor connection quality	0	
0		1	1	Connection broken	0	
15 to 0	1 to 0	1	1	Connection broken	0	

Table 35: Values for quality monitoring and RSSI

Frequent errors can indicate that the shielding design of the DSL connection is inadequate or that the cable does not comply with the specification.

The slave RSSI register (see section 5.5.2) contains the **SRSSI** value that lies in the range between "0" and "7". **SRSSI** indicates the quality of the run time connection as the signal strength of the data transmitted to the DSL encoder.

6.3. Fast position

The fast position and the rotation speed of the encoder shaft are transmitted on the DSL motor feedback system process data channel. These values are the main process values for the drive application control circuit.

HIPERFACE DSL® stores the fast position in the `POS0…4` DSL Master registers and the rotation speed in the `VEL0…2` registers.

The position is given as a 40 bit value that includes the angle setting ("single turn" value) and the number of rotations ("multi-turn" value). Only the position bits actually measured by the motor feedback system are accessible and are stored in the registers as a right-justified value. The other (higher value) bits are constantly set at "0" (see examples "a" to "c" in Figure 25).

The fast position is automatically added to the current safe position of the motor feedback system. This mechanism is automatically checked by the DSL Master. For this purpose, the DSL Master compares the fast with the safe position (see section 6.4).

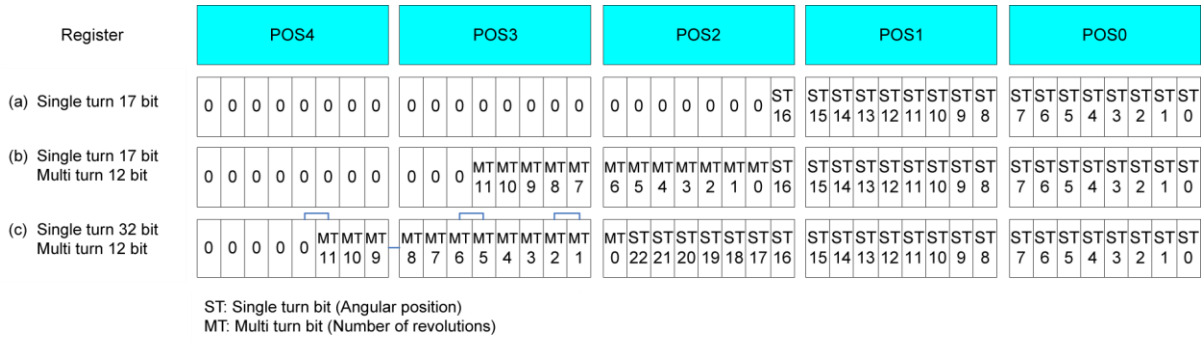


Figure 25: Position value format

The motor feedback system fast position is sampled and transmitted if the DSL Master receives a SYNC signal. This SYNC signal can be created in two different ways (see sections 6.3.1 and 6.3.2).

If the encoder detects faults in the fast position sensor or if a transmission fault of the fast position value occurs, the fast position registers `POS0…4` and the rotation speed registers `VEL0…2` are automatically loaded with estimator values to allow for a ride-through of non-permanent fault conditions. This state is indicated by a non-zero value in the `MAXDEV` registers and a raised `pos_estimated` signal.

6.3.1. Free running mode

In free running mode, the SYNC signal is automatically created by the DSL Master, for which the maximum frame transmission frequency is used (see Table 8). The free running mode is the standard DSL Master operating mode at start-up.

This operating mode can also be selected manually, by setting the **ES** value in the `SYNC_CTRL` register to "0".

It should be noted that in free running mode, no account is taken of the signals at the SYNC input.

The polling of the position and rotation speed values is explained in Figure 26 and Figure 27.

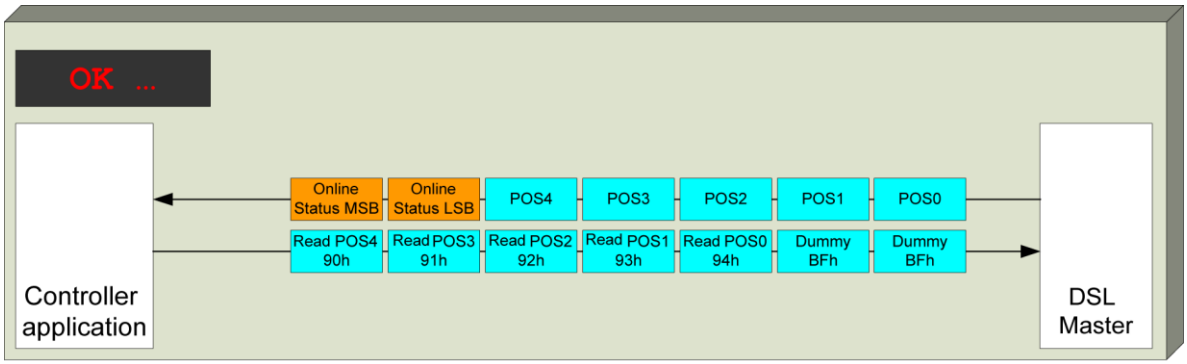


Figure 26: Polling of position registers in free running mode

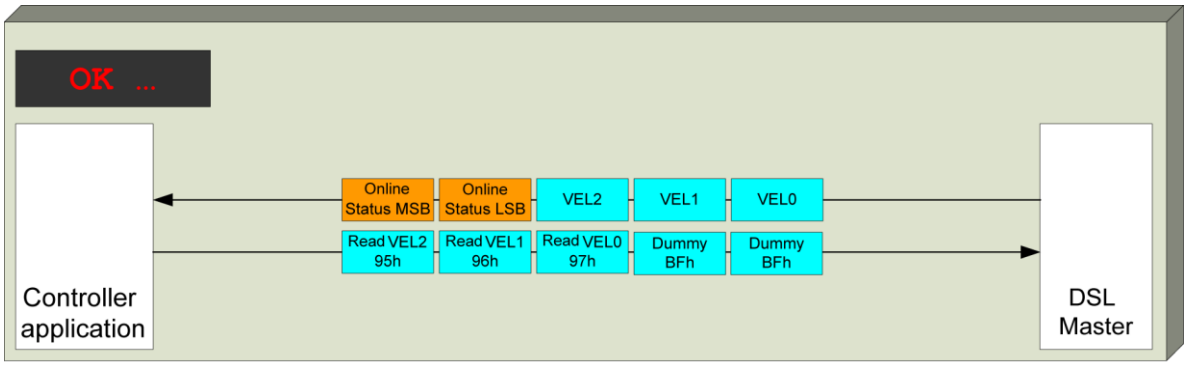


Figure 27: Polling of rotation speed registers in free running mode

6.3.2. SYNC mode

In SYNC mode, the DSL Master depends on a prepared cyclic control signal. This control signal triggers position measurements and enables polling of position and rotation speed values synchronously with the control signal. The control signal must be applied to the SYNC input and have the characteristics prescribed for the DSL Master (see section 3.2).

The position is available after a set delay in relation to the leading edge of the control signal.

When SYNC mode is used the following points must be noted:

1.) A correct control signal must be applied at the `sync` input. The signal must correspond with the specifications for pulse width and cycle time.

2.) Setting or deleting the **SPOL** bit in the `SYS_CTRL` register determines whether the position measurements are to be triggered by the leading of the trailing edge of the control signal. The set latency of the DSL system is measured from this edge.

3.) The correct **ES** divider must be set in the `SYNC_CTRL` register. This divider determines how many position samplings and transmissions will be undertaken for each control signal.

CAUTION

The ES **divider must be selected so that the cycle time between the two position samplings corresponds to the prescribed range limits (package cycle time) in** Table 8**.**

The range limits for the **ES** divider can be calculated as follows:

$$\mathbf{ES} \leq t_{Sync} / t_{Min}$$

$$\mathbf{ES} \geq t_{Sync} / t_{Max}$$

The symbols used in the formulae are explained as follows:

Symbol	Description
t_{Sync}	Cycle time of the pulse signal at the SYNC input
t_{Min}	Minimum cycle time for the transmission of DSL frames (11.95 µs)
t_{Max}	Maximum cycle time for the transmission of DSL frames (23.90 µs)

Table 36 below contains typical cycle times for the control signal and the valid ranges of **ES** divider values.

Frequency of the SYNC signal (kHz)	Cycle time of the SYNC signal (µs)	Minimum value ES	Maximum value ES
2	500	21	41
4	250	11	20
6.25	160	7	13
8	125	6	10
16	62.5	3	5
40	25	2	2
42 to 83	23.9 to 12,1	1	1

Table 36: Cycle times for SYNC signals and valid ES values

After the sequence described above, SYNC mode is activated. In the prescribed "start-up time" (see Table 8) the protocol is synchronized with the applied `sync` signal. Following this period, the position value is available with constant latency after the data package has been transmitted (see Figure 29).

The time profile of the relevant signals in SYNC mode is shown in the following graphic. This shows the `sync` signal, the `cycle` signal generated from the **ES** divider and the `dsl_out` DSL output signal.

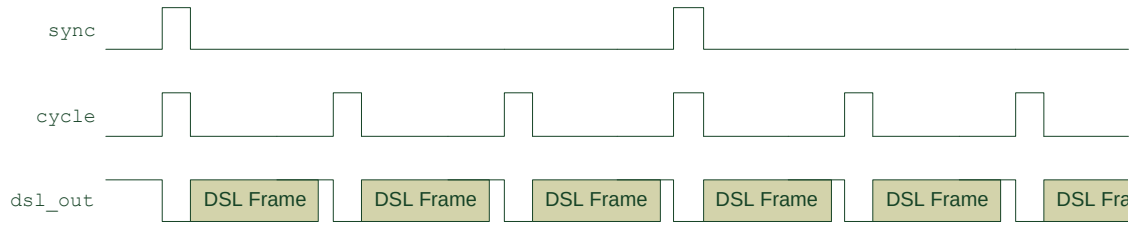


Figure 28. SYNC mode signals.The arrival of a requested fast position is indicated by the **POSTX** Online Status bits of Interfaces 1 and 2 (see section 5.2.1).

The position value can be polled via Interface 1 from the `POS0 to 4` registers of the DSL Master (see section 5.3.11).

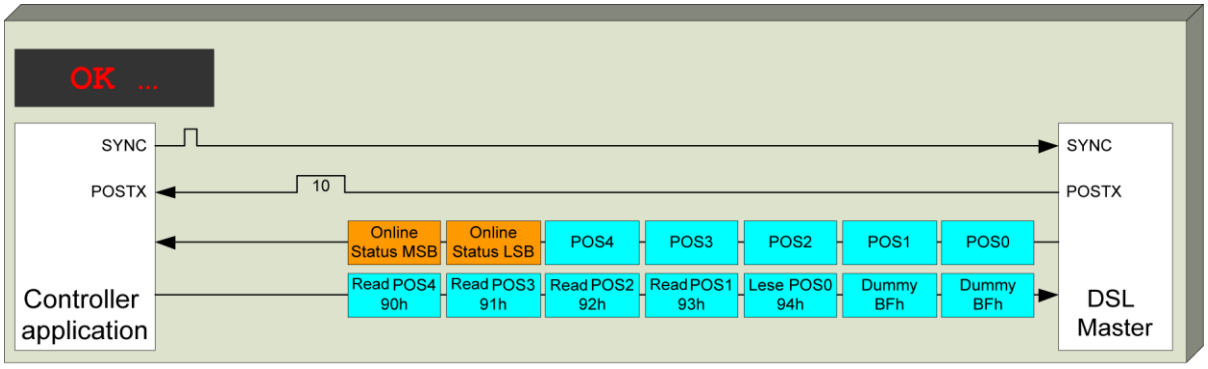


Figure 29: Polling registers for the fast position in SYNC mode.

It should be noted that polling of fewer than the five full position registers may be appropriate dependent upon the application. This enables fast reading of the position.

The rotation speed of the motor feedback system can be read in the same way. The rotation speed is also measured and transmitted synchronously with the `sync` signal. This is explained in Figure 30.

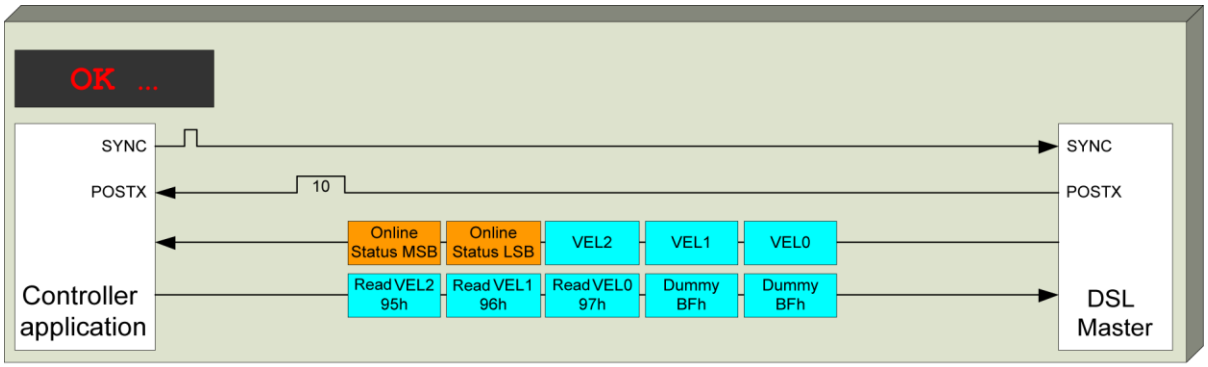


Figure 30: Polling of rotation speed registers in SYNC mode.

6.4. Safe position, Channel 1

The motor feedback system safe position is not only transmitted incrementally (see section 6.3), but also as a complete safe position. This makes internal validation of the data transfer possible.

The complete safe position is transmitted in every eighth protocol frame and is therefore slower than the fast position.

CAUTION

The safe position is not synchronized with the last control cycle present at the DSL Master IP Core. The safe position should not be used in the control circuit for drive position or speed.

The safe position is stored in the `VPOS0…4` registers and can be polled via Interface 1 (see Figure 31).

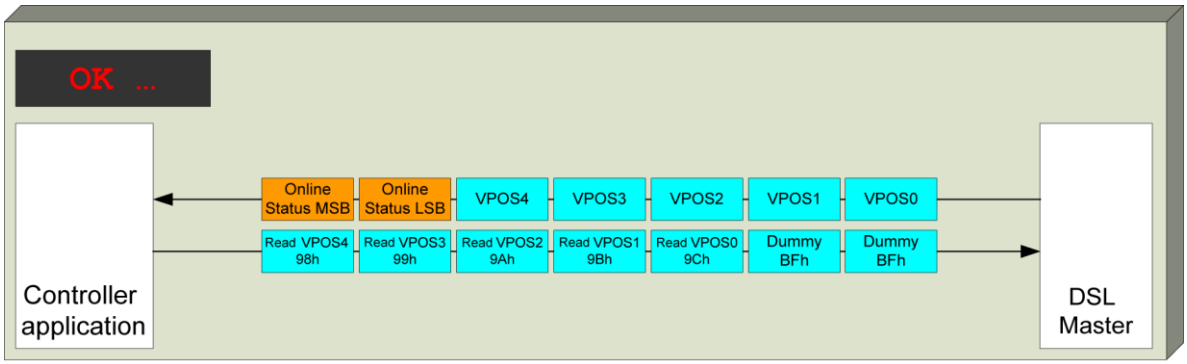


Figure 31: Polling the safe position

As soon as the DSL master identifies a difference between the transmitted safe position and the integrated fast position, the **POS** error bit is set in the `EVENT_H` register (see section 6.5).

6.5. Safe position, Channel 2

For safety-related applications there is a second channel for the safe position. This Channel 2 acts as redundancy for the identification of errors in the DSL motor feedback system.

The Channel 2 safe position originates from various sources dependent upon the configuration of the DSL motor feedback system (see Table 37).

DSL encoder safety architecture	Source of the safe position on Channel 2	Safe position, Channel 2, resolution
Category 2 (SIL 2) (one sensor, internal diagnostics)	As Channel 1, different transmission of position data	As Channel 1
Category 3 (SIL 3) (two sensors)	Separate sensor from Channel 1	Dependent on separate sensor (less than or same as Channel 1)

Table 37: Source of the safe position on Channel 2

The resolution of Channel 2 for the safe position may be less than the resolution of Channel 1 if a second sensor in the DSL motor feedback system with a lower performance than the main sensor is used.

It should be noted that in this case, the cross check with both safe positions of Channel 1 and Channel 2 must be limited to a total of higher value position bits given in the product data sheet.

The cross check of Channel 1 and Channel 2 safe positions is not carried out internally in the DSL Master IP Core. Due to the safety architecture of an FPGA, this check must be undertaken by electronic components outside the FPGA that contain the IP Core.

The complete Channel 2 with the safe position is transmitted in every eighth protocol frame and synchronously with Channel 1 with the safe position.

Channel 2 with the safe position is stored in the `VPOS20 to 4` registers and can be polled via Interface 2 (see Figure 32).

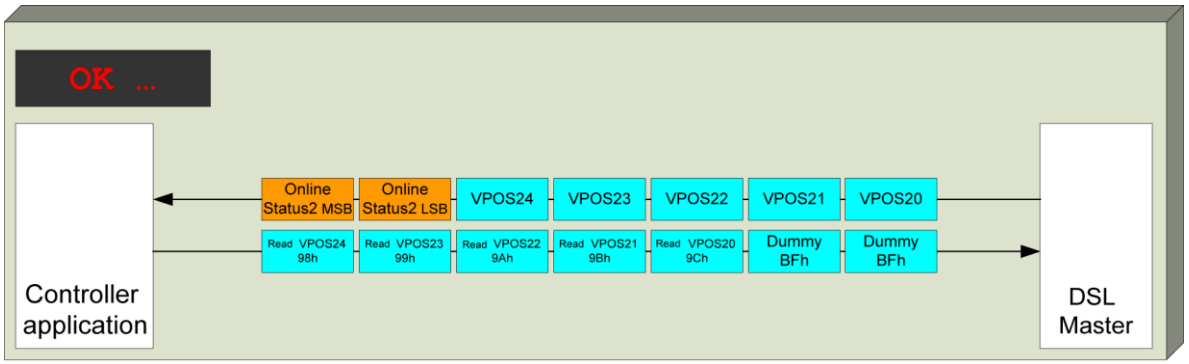


Figure 32: Polling Channel 2 with safe position

6.6. Parameters Channel

The HIPERFACE DSL® Parameters Channel is for access to the motor feedback system parameters.

Using two separate access mechanisms, the Parameters Channel distinguishes between two separate data areas:

- Interface information is polled via "short messages".
- Information on the motor feedback system is polled via "long messages".

6.6.1. Short message

Remote (DSL motor feedback system) registers that indicate interface information are mirrored in the DSL Master under register addresses 40h to 7Fh. These remote registers are addressed in the same way as DSL Master registers.

As the values of remote registers are transmitted via the Parameters Channel and hence via the DSL cables, the delay between polling and answer for "short message" transactions depends on the connection cables of the systems in question. Unlike DSL Master registers, the frequency inverter application must wait for the answer to arrive.

Although remote registers are addressed in the same way as DSL Master registers, the answer is recorded in a special DSL Master register (`PC_DATA`, 2Fh).

The value of the direct answer that reaches SPI1 MISO during reading or writing is a dummy value.

In the `EVENT_L` DSL Master register, **FRES** indicates whether the "short message" channel is busy or whether the answer has reached the DSL Master. **FRES** can be evaluated for all SPI1 operations as the register content is a component of every SPI1 transmission (bit 0 in **ONLINE STATUS L**, see section 5.2.1).

The Parameters Channel can only transmit one "short message" at a time. Several remote registers can only be polled in sequence, i.e. after the previous answer has been received.

It should be noted that a "short message" can be triggered during a running "long message" transaction (see section 6.6.2) and vice versa.

The following figure gives an example of reading from the remote register `ENC_ST0` (40h).

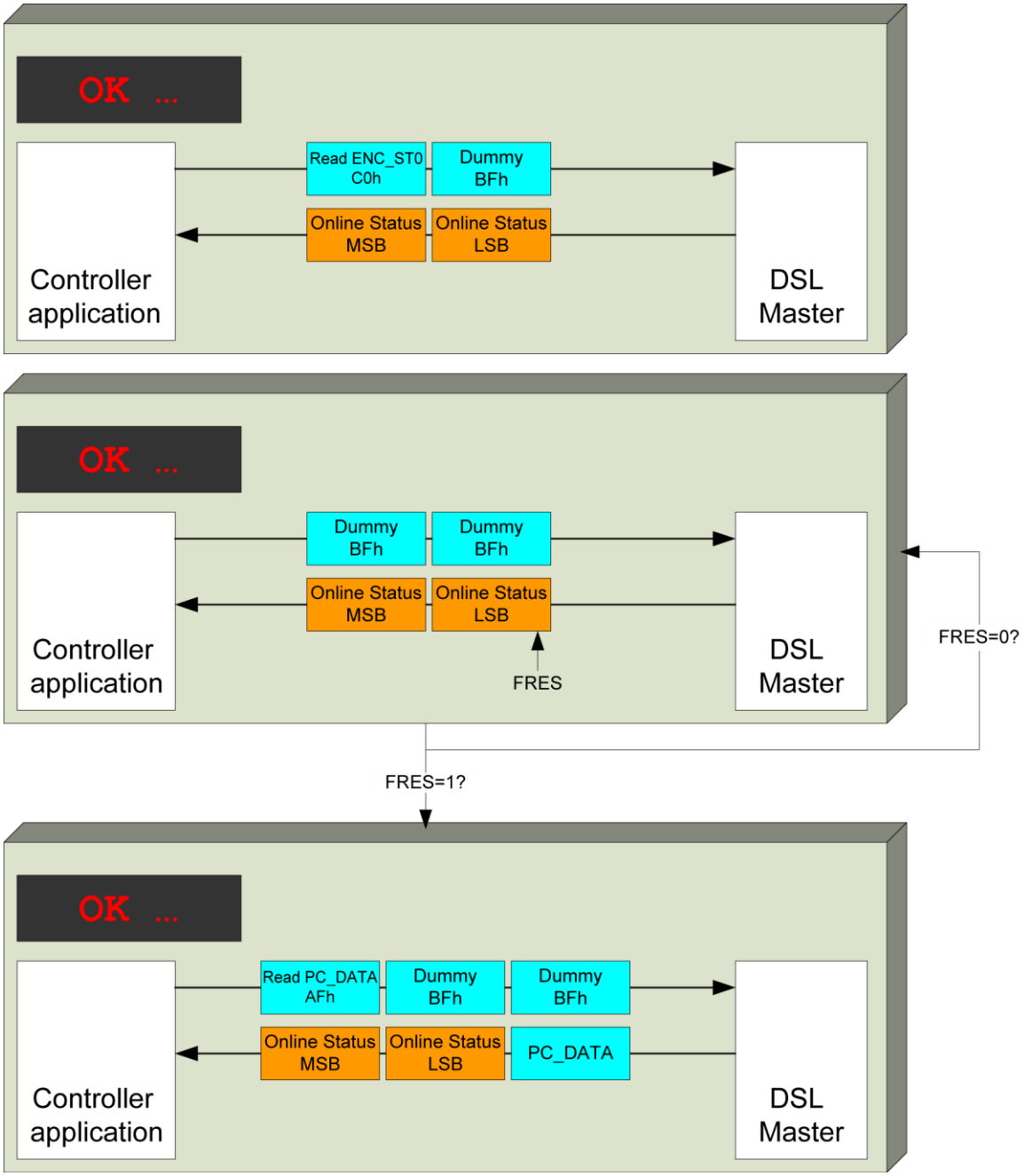


Figure 33: Reading from remote register

6.6.2. Long message

Apart from the interface registers (see section 5.5), access to resources of the motor feedback system takes place by "long message" transactions on the Parameters Channel.

The organization and scope of the resources depend on the particular DSL Slave and DSL encoder installation.

A "long message" is triggered by setting the corresponding "long message" registers (PC_ADD_H/L, PC_OFF_H/L, PC_CTRL and – for write operations – PC_BUFFER0:7). The result, where present, is recorded in the PC_BUFFER0:7 registers.

When carrying out a long message transaction, **FREL** is deleted in the EVENT_L register. When the transaction has completed, **FREL** is set again.

It should be noted that a "long message" can be triggered during a running "short message" transaction (see section 6.6.1) and vice versa.

A "long message" transaction enables the exchange of general parameter data between the frequency inverter and the motor feedback system. These parameters can contain information on the status of the motor feedback system, control data for the motor feedback system or user-defined data.

Individual parameters are defined as resources of the motor feedback system.

Chapter 7 lists the usual resources of a DSL encoder. Resources that have actually been installed are specified in the data sheet for individual DSL encoders.

A "long message" is triggered by the setting of the corresponding PC_BUFFER, PC_ADD, PC_OFF and PC_CTRL (20h to 2Ch) registers in the DSL Master.

Whilst the motor feedback system is processing a "long message", the **FREL** flag in the EVENT_L (05h) events register is deleted. Once the processing is finished, this flag is set once more to indicate readiness to process a fresh "long message".

After the setting of a **FREL** flag has been indicated, the data returned from a read access can be polled in the PC_BUFFER registers (see section 5.3.16).

It should be noted that only one "long message" can be processed at a time. Access to resources with more than 8 bytes must be done using successive "long messages".

A "long message" is defined with the aid of several characteristics present in the registers quoted above. The figure below gives an overview of these characteristics.

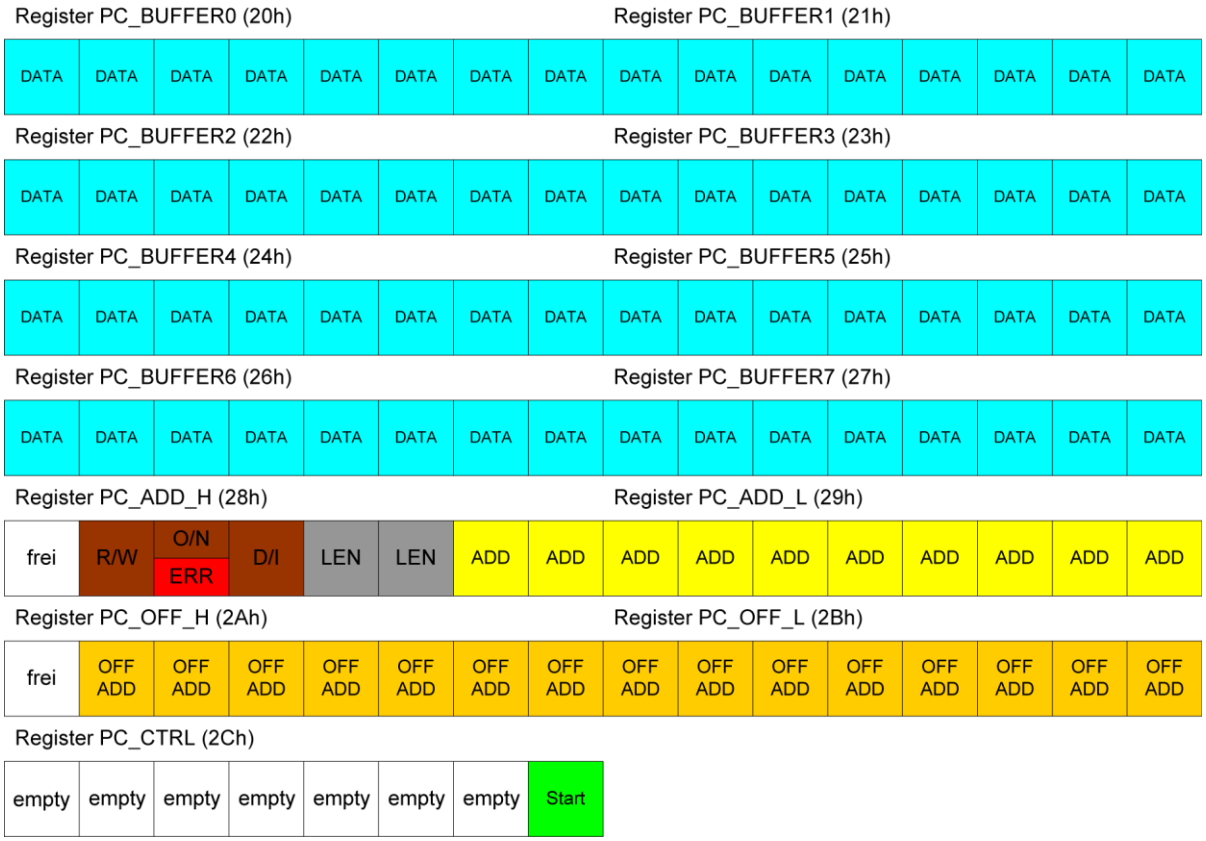


Figure 34: "Long message" characteristics

The meaning of each characteristic is described in the table below.

Characteristic	Description
DATA	Content of the "long message"
R/W	Direction of the "long message" (read/write)
O/N	Only for triggering the message: "Long message" mode (with offset/without offset)
ERR	Only for answer to the message: Error indication
D/I	"Long message" mode (direct/indirect addressing)
LEN	Data length of the "long message" (0/2/4/8 bytes)
ADD	Identification/address of the resource for a "long message"
OFF ADD	Offset address of the resource for a "long message"
Start	Trigger for the transmission of the "long message"

Table 38: "Long message" characteristics

DATA contains all the data to be transmitted during write access to the motor feedback system. After a read access, **DATA** contains all the data from the motor feedback system.

Dependent upon the **LEN** characteristic, separate areas of the **DATA** register are used.

LEN value	Data length	DATA register used
0 (00b)	0 bytes	No data transfer
1 (01b)	2 bytes	PC_BUFFER0 PC_BUFFER1
2 (10b)	4 bytes	PC_BUFFER0 PC_BUFFER1 PC_BUFFER2 PC_BUFFER3
3 (11b)	8 bytes	PC_BUFFER0 PC_BUFFER1 PC_BUFFER2 PC_BUFFER3 PC_BUFFER4 PC_BUFFER5 PC_BUFFER6 PC_BUFFER7

Table 39: DATA register areas

The **R/W** "long message" characteristic is used to determine whether a read or write access is programmed.

R/W value	Direction of the "long message"
0	Write
1	Read

Table 40: R/W value for the "long message"

For programmed write access, the data to be transferred must be present in the **DATA** characteristic.

The "long message" characteristic **O/N** determines whether the message is transmitted with or without an offset address.

O/N value	"Long message" mode
0	No offset addressing
1	Offset addressing

Table 41: O/N value for the "long message"

The resource description in section 7.2 contains an explanation of the purpose for which offset addressing is used. Using offset addressing, an additional "long message" parameter can be transmitted to the motor feedback system as well as the address (**ADD**) and the message data (**DATA**).

If the **O/N** characteristic is set to "1", then the **OFF ADD** characteristic must contain the value for the offset address characteristic.

The same **O/N** bit in the **PC_ADD_H** register can be read after receipt of the "long message" answer to determine the **ERR** error characteristic.

ERR value	Error during resource access
0	No error
1	An error was identified

Table 42: ERR value for the "long message"

If the motor feedback system discovers an error during a resource access, the **ERR** bit is set and the **LEN** characteristic is set to 2 bytes (01b).

In this case the PC_BUFFER0 and PC_BUFFFER 1 **DATA** registers will contain an error code as detailed in section 6.7.5. This error code enables precise error handling for "long messages".

D/I determines whether direct or indirect addressing is used for a "long message".

D/I value	"Long message" addressing
0	Direct addressing
1	Indirect addressing

Table 43: D/I value for the "long message"

The resource description in section 7.2 contains an explanation of the purpose for which direct or indirect addressing is used.

The **LEN** characteristic determines the data length of the "long message". Table 39 describes the use of this characteristic.

LEN must correspond to the permitted values applicable to the resource addressed (see section 7.2). If these values are not observed, the "long message" in the motor feedback system will be ended and a corresponding error message indicated.

The **ADD** characteristic determines the target resource of the "long message". The **ADD** value corresponds to the RID resource index.

ADD value	Resource index (RID)
000h to 3FFh	000h to 3FFh

Table 44: ADD value for the "long message"

Access to resources not installed in the motor feedback system is ended with a corresponding error message.

The **OFF ADD** "long message" characteristic contains the offset address, provided offset addressing is used (see above under the **O/N** characteristic). The resource description in section 7.2 contains an explanation of the permitted scope and purpose of each individual resource.

OFF ADD value	Register used
0000h to 7FFFh	PCR_ADD_H/PCR_ADD_L

Table 45: OFF ADD value for the "long message"

Access to a resource with an invalid **OFF ADD** value, or one that is too high, will cause the "long message" in the motor feedback system to be ended and a corresponding error message will be indicated.

The table below gives an example of a "long message" read command.

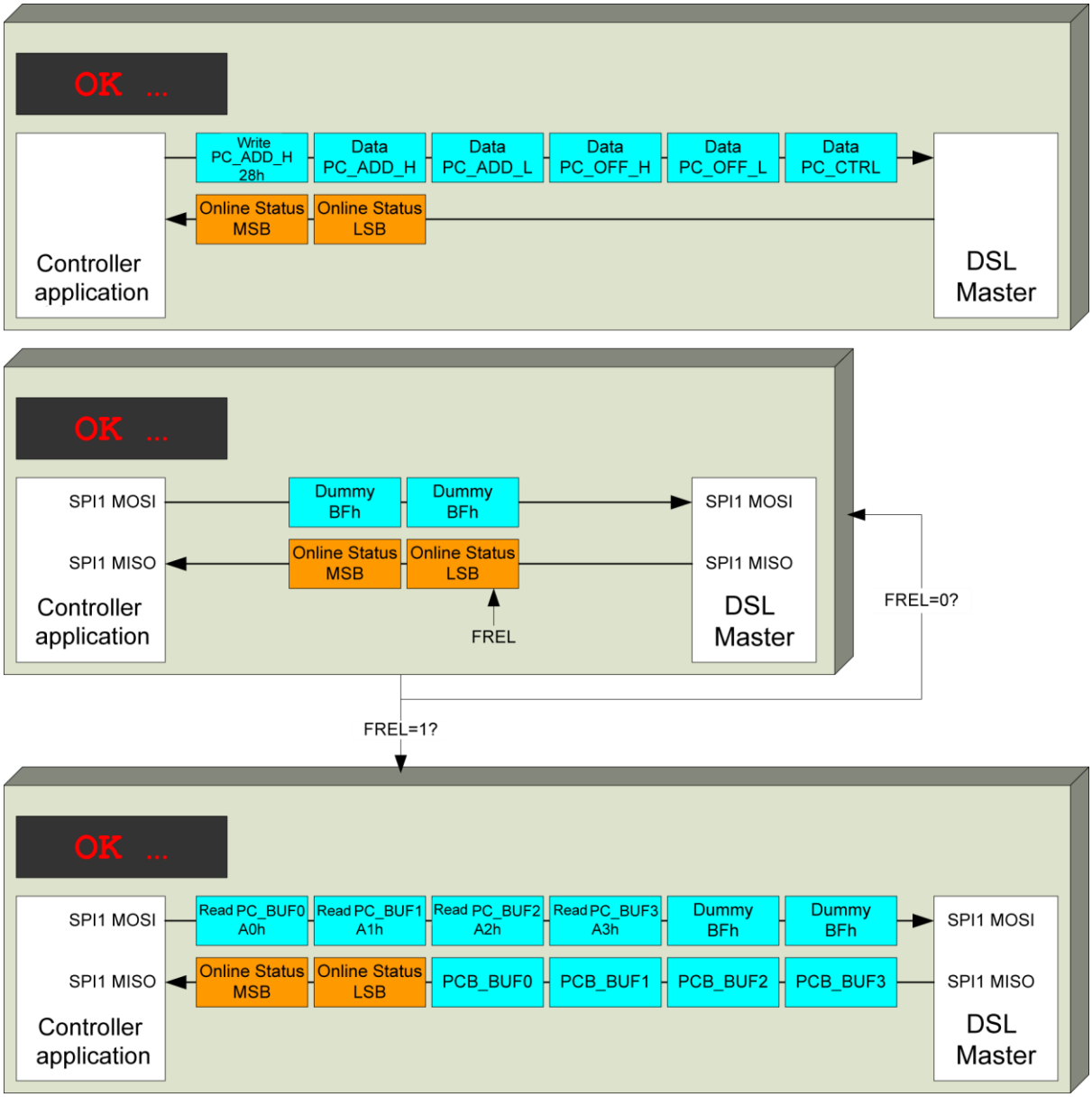


Figure 35: Example of a "long message" read command

6.6.3. Error handling in the Parameters Channel

Errors in a "short message" are handled differently than for a "long message".

If a "short message" is transmitted to the motor feedback system with an error, the protocol sends the message again automatically until an acknowledgment of correct transmission is received. This is not explicitly indicated to the frequency inverter. The **FRES** flag remains deleted until correct receipt of the answer to the "short message".

If the DSL Master receives no acknowledgment of the transmission of a "short message", the protocol automatically begins cyclic repetition of the transmission. This time overrun of a "short message" is indicated by the **RET** flag in the `EVENT_L` event register and in the Online Master status. **RET** is only deleted automatically after correct receipt of the answer to the "short message".

If a "long message" is transmitted to the motor feedback system with an error, this is indicated by the **ANS** flag in the `EVENT_L` event register. The "long message" is not transmitted again automatically.

If the DSL Master receives no acknowledgment of the transmission of a "long message", the protocol automatically begins cyclic repetition of the transmission. This time overrun of a "long message" is indicated by the **RET** flag in the `EVENT_L` event register and in the Online Master status. **RET** is only deleted automatically once the acknowledgment of the transmission of the "long message" has been correctly received.

If a "long message" was correctly transmitted to the motor feedback system, but the answer to the frequency inverter application is missing or arrives too slowly, the DSL Master does not repeat the transmissions automatically. This is necessary as the processing time for a "long message" cannot be predicted. To determine the time overrun for a running "long message", the frequency inverter application can refer to the time overrun characteristic in each individual resource of the DSL motor feedback system (see section 7.2).

To be able to use the Parameters Channel again even though an unanswered "short message" or "long message" is blocking the corresponding message channel, the frequency inverter application must trigger a reset of the Parameters Channel.

This reset does not affect position measuring or the transmission of position data.

The reset sequence for the Parameters Channel is specified in section 4.5.

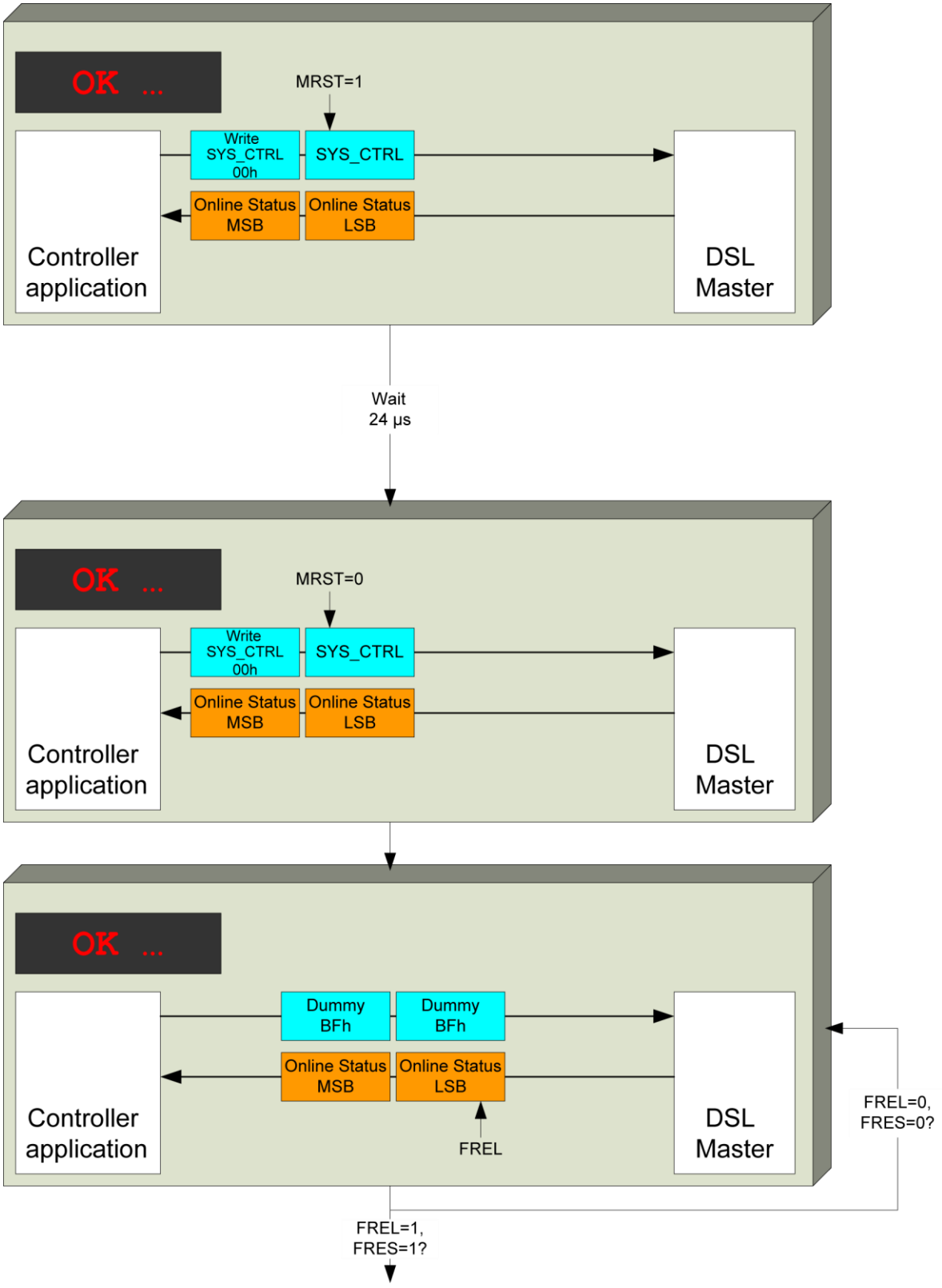


Figure 36: Reset of the Parameters Channel

6.7. Status and error messages

HIPERFACE DSL® can be used to monitor the status of the motor feedback system in various ways.

Dependent upon the importance of the status or error message, different indication mechanisms are used to inform the frequency inverter application.

6.7.1. Event register

The EVENT_H and EVENT_L registers (see section 5.3.4) contain all important error and status indications for the DSL Master. All events are updated after 200 µs at the latest.

More specifically, the EVENT_H register contains all the critical motor feedback system error messages. Recommendations for error handling can be found in section 5.3.4.

The EVENT_L register contains all motor feedback system warning and status messages. Recommendations for error handling can be found in section 5.3.4.

All errors and warning conditions indicated in the event registers must be acknowledged by deletion of the corresponding error bits. The DSL Master does not automatically reset these bits.

This mechanism is explained below using an example (error in the transmitted fast position, **POS** bit).

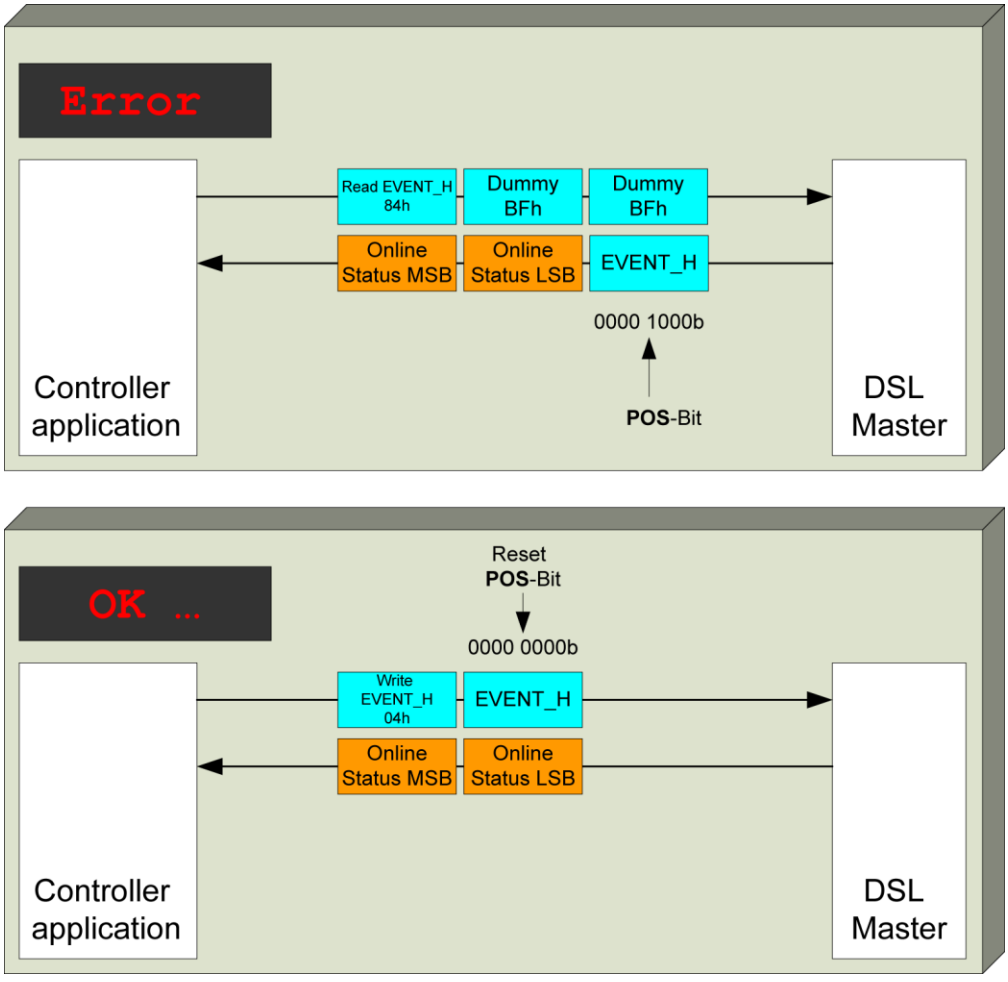


Figure 37: Acknowledgment of event bits

In the frequency inverter application, three mechanisms can be installed to allow timely reaction to reports in the event registers.

- These registers are polled cyclically.
- The Online Status is polled cyclically. Event registers are mirrored here (see section 6.7.2).
- Either all, or individual event register events can be masked in the event mask registers (registers `MASK_H` and `MASK_L`, see section 5.3.5), in order to issue events via the `interrupt` interface (see section 4.4.2).

6.7.2. Online Status

The Online Status 1 and 2 (see section 5.2) is transmitted during every communication via Interface 1 or 2 between the frequency inverter application and the DSL Master. The status contains the error and status reports from the event registers.

Unlike with direct polling of the event registers, the Online Status only shows the current status values. As soon as the error status of the motor feedback system becomes unavailable, the error is no longer indicated in the Online Status.

The event registers retain the error statuses until the registers are acknowledged. After acknowledgment, the event registers are reset (see section 5.3.4).

The Online Status is updated after 200 µs at the latest.

6.7.3. Status summary of the motor feedback system

In addition, detailed motor feedback system errors and warnings are indicated in the SUMMARY status summary register (18h, see section 5.3.13).

Each individual bit of the register indicates an error status of a functionality in the motor feedback system (see Table 46). The safety relevance of all of these error groups is precisely described in this table.

An error indication with critical safety relevance always requires a corresponding reaction. If no further diagnostics are carried out, after the indication of a safety-critical error a safe condition of the drive system must be achieved (e.g. emergency stopping of the motor).

Bit no.	Error group	Safety relevance
0	1 = Fast position error	Critical for functions with safe rotation speed
1	Safe position error	Critical for functions with safe position
2	Installation error	Critical for all safety functions
3	Monitoring error	Warning for all safety functions
4	Error when accessing a resource	Not safety-critical
5	Reserved	
6	Reserved	
7	User-defined warnings	Not safety-critical

Table 46: Motor feedback system error groups

A bit set in the status summary register definitely indicates that one or more individual errors in the motor feedback system have been recognized. The individual errors can be determined by polling the remote encoder status register ENC_ST (see sections 5.5.1 and 6.7.4).

It should be noted that the **SUM** error bit in the EVENT_H event register represents an aggregated summary of all error groups (see section 5.3.5).

It should be noted that the reading of detailed motor feedback system error messages enables a more precise reaction to all fault indications in the status summary.

6.7.4. Motor feedback system error messages

Errors recognized in the motor feedback system are indicated in the ENC_ST remote encoder status registers.

Access to a remote encoder status register can last up to 1.2 ms.

A summary of error groups is indicated at the appropriate time in the status summary register in the DSL Master (see section 6.7.3).

To simplify error handling, the motor feedback system errors are grouped logically.

Table 47 below contains all error messages and recommendations for error handling.

Error group (Register)	Error bit	Description	Error handling
0 (40h)	0	Protocol reset indication	**After an encoder has been switched on, this message is always displayed and should be reset.** **If this error is displayed later, it is probable that the position and rotation speed of the encoder are wrong.** Automatic communications restart. If this error appears repeatedly, check the cable connection. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	1	Acceleration overrun	**Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** Action: Restart the encoder. If "Acceleration overrun" is indicated, the encoder experienced an acceleration outside the HIPERFACE DSL specification.
	2	Test running The frequency inverter system has requested a test. All error indications arising from this test are indicated together with the message "Test running" to be able to distinguish this indication from actual errors.	If the message "Test running" is shown together with an error indication arising from a previous test message, no action is required apart from having to delete this bit and the corresponding error bit. If the message "Test running" is shown without the expected error indication, there is probably a safety related error in the DSL encoder. **In this case the drive system must be placed in a safe condition.** Action: Restart the encoder. If the error condition persists, there is probably a general hardware or mechanical failure. Inform customer service.
	4	Position error: Error in tracking filter	**Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** **The drive system must be placed in a safe condition.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.

Error group (Register)	Error bit	Description	Error handling
	5	Position error: Error in the vector length	**Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** When there is an error, the IP Core advances the fast position in linear fashion until valid values are present again. Dependent upon the application, one or more vector length errors in succession can be tolerated. The tolerable number of errors (possibly application-dependent) can be determined from a calculation of the maximum deviations in each error that occurs. If necessary, the safe position can be used as an alternative to position measurement if this error arises for the fast position. In this case the significantly slower refresh cycle of the safe position must be considered. **If the maximum tolerable number of errors is exceeded, the drive system must be placed in a safe condition.** If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	6	Position error: Counter error	**Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** **The drive system must be placed in a safe condition.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	7	Position error: Synchronization error	**Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** **The drive system must be placed in a safe condition.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.

Error group (Register)	Error bit	Description	Error handling
1 (41h)	0	Error in Single Turn	**Following the indication of this error, it is probable that the position of the DSL encoder is wrong.** **The drive system must be placed in a safe condition if a safe position function is being used.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	1	Error 1 in Multi-Turn	**Following the indication of this error, it is probable that the position of the DSL encoder is wrong.** **The drive system must be placed in a safe condition if a safe position function is being used.** Action: Restart the encoder. Check the allocation between encoder and motor. Check the magnetic environment of the encoder. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	2	Error in Multi-Turn, gear stage 2	**Following the indication of this error, it is probable that the position of the DSL encoder is wrong.** **The drive system must be placed in a safe condition if a safe position function is being used.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.
	3	Error in Multi-Turn, gear stage 3	**Following the indication of this error, it is probable that the position of the DSL encoder is wrong.** **The drive system must be placed in a safe condition if a safe position function is being used.** Action: Restart the encoder. Check the allocation between encoder and motor. If the error persists, there is probably a general hardware or mechanical failure. Inform customer service.

Error group (Register)	Error bit	Description	Error handling
2 (42h)	0	Switch-on self test	**Only for DSL safety encoders:** **Must be set after switching on.** Action: Reset after report. If the report persists or is not set after switching on **it is probable that the position and rotation speed of the encoder are wrong.** **The drive system must be placed in a safe condition.**
	1	Safety parameters warning	**Only for DSL safety encoders:** After switching on, errors were found in the safety parameters that were rectified. No further action necessary, reset after report. If the warning persists, there is probably a memory error or a general hardware fault. Inform customer service.
	2	Safety parameters error	**Only for DSL safety encoders:** **Following the indication of this error, it is probable that the position and rotation speed of the encoder are wrong.** **The drive system must be placed in a safe condition.** Action: Restart the encoder. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
	3	Standard parameters error	After switching on, errors were found in the standard parameters. Data (except position) given by the encoder may be wrong. Action: Restart the encoder. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
	4	Internal communications error 1	After switching on, an internal communications error was identified. Action: If no other error is indicated, no further action is necessary. Reset after report. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
	5	Internal communications error 2	After switching on, an internal communications error was identified. Action: If no other error is indicated, no further action is necessary. Reset after report. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
	6	Internal system error	After switching on, an internal electronic error was identified. Action: Restart the encoder. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.

Error group (Register)	Error bit	Description	Error handling
3 (43h)	0	Critical temperature	Cool or warm the encoder. Check the installation position of the encoder.
	1	Critical LED current	The encoder LED is defective or fatigued. Internal mechanical damage. Inform customer service.
	2	Critical supply voltage	Encoder hardware defect. Inform customer service.
	3	Critical rotation speed	Rotation speed limit prescribed in the data sheet exceeded. Check the application.
	4	Critical acceleration	Acceleration limit prescribed in the data sheet exceeded. Check the application.
	5	Counter overrun	Reset the counter
	6	Internal monitoring error	An internal error was identified during a monitoring operation. Action: Restart the encoder. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
4 (44h)	0	Invalid argument during access to a resource	Check the programming of the frequency inverter application.
	1	Access to resource denied	Check the programming of the frequency inverter application. Set the correct access code.
	2	Error when accessing an internal resource	Restart the encoder. If the error persists, there is probably a memory error or a general hardware fault. Inform customer service.
	3	Error when accessing a file	Check the programming of the frequency inverter application.
7 (47h)	0 to 7	User-defined warnings	Relevance of the warning dependent upon user-defined warning limits (see section 7.2.4.5). The number of available user-defined warnings is specified in the product data sheet.

Table 47: Motor feedback system error messages

6.7.5. Long message error code

Due to the complexity of "long messages", errors occurring here are reported in detail to the user.

If the motor feedback system establishes an error when accessing a resource, this error is displayed as an error message (see section 6.7.4). In addition the **ERR** flag is set, the **LEN** characteristic is set to 2 bytes (01B) and the `PC_BUFFER0` and `PC_BUFFER1` DATA registers contain an error code.

By means of this error code, the errors in a "long message" transaction can be understood in detail.

The table below contains the error codes and their meaning.

It should be noted that the value of the `PC_BUFFER1` register corresponds to the error code in the `ENC_ST` encoder status register (see section 5.5.1).

PC_BUFFER1	PC_BUFFER0	Meaning of the error code
40h	10h	Resource address not installed in the encoder
	11h	Incorrect length for resource access given
	12h	Incorrect length for direct resource access given
	13h	Offset address too high
	14h	Invalid offset address
	15h	Invalid "long message" characteristic
	16h	Missing offset address
41h	10h	Write access not possible
	11h	Read access not possible
	12h	Write access denied
	13h	Read access denied
	14h	Write access for direct resource access denied
42h	10h	Resource database entry damaged
	11h	Time overrun during resource access
	12h	Internal processing error during resource access
43h	11h	File name was not found
	12h	Invalid address for file access
	13h	File size may not be altered
	14h	Memory location for files full
	15h	File allocation table damaged
	16h	No file loaded for action
	17h	File exists with the same name

Table 48: "Long message" error codes.

7. Motor feedback system resources

The resources of a DSL motor feedback system make up most of the functions of the sensor.

"Long message" transactions enable access to all resources installed in a DSL motor feedback system. Examples of resources are the values for encoder designation, function and fault monitoring, sensor administration or the storage of user-defined data.

It should be noted that for motor feedback system process values, i.e. position and rotation speed values, separate access mechanisms apply (see sections 6.3 and 6.4).

The resources installed in a DSL motor feedback system are accessible via the resources database (RDB). A "long message" is always aimed at an individual RDB entry.

The resources set out in this section describe the normal functions of a DSL motor feedback system. The actual resources installed in individual DSL motor feedback systems are given in the appropriate data sheets.

7.1. Access to resources

Access to the resources of a DSL motor feedback system is possible in two ways. This section also describes how resource definitions can be read by "direct access".

7.1.1. Access by means of an index

Each individual resource is defined by a unique resource index (RID).

A "long message" can be directed at the associated resource by using the RID as the address characteristic (see section 6.6.2).

If a resource is accessed via direct access, the resource definition is returned (see section 7.1.3).

7.1.2. Access using the tree

The resources database (RDB) is structured in the form of a tree. This enables access to a resource by referencing, in which the access begins with a root resource that returns an indicator to other resources. Figure 38 shows this tree structure.

Starting at the "root node" resource with the resource index RID=000h, a write access returns the addresses of the linked nodes. By progressing recursively through further nodes, it is possible to access all levels of the tree.

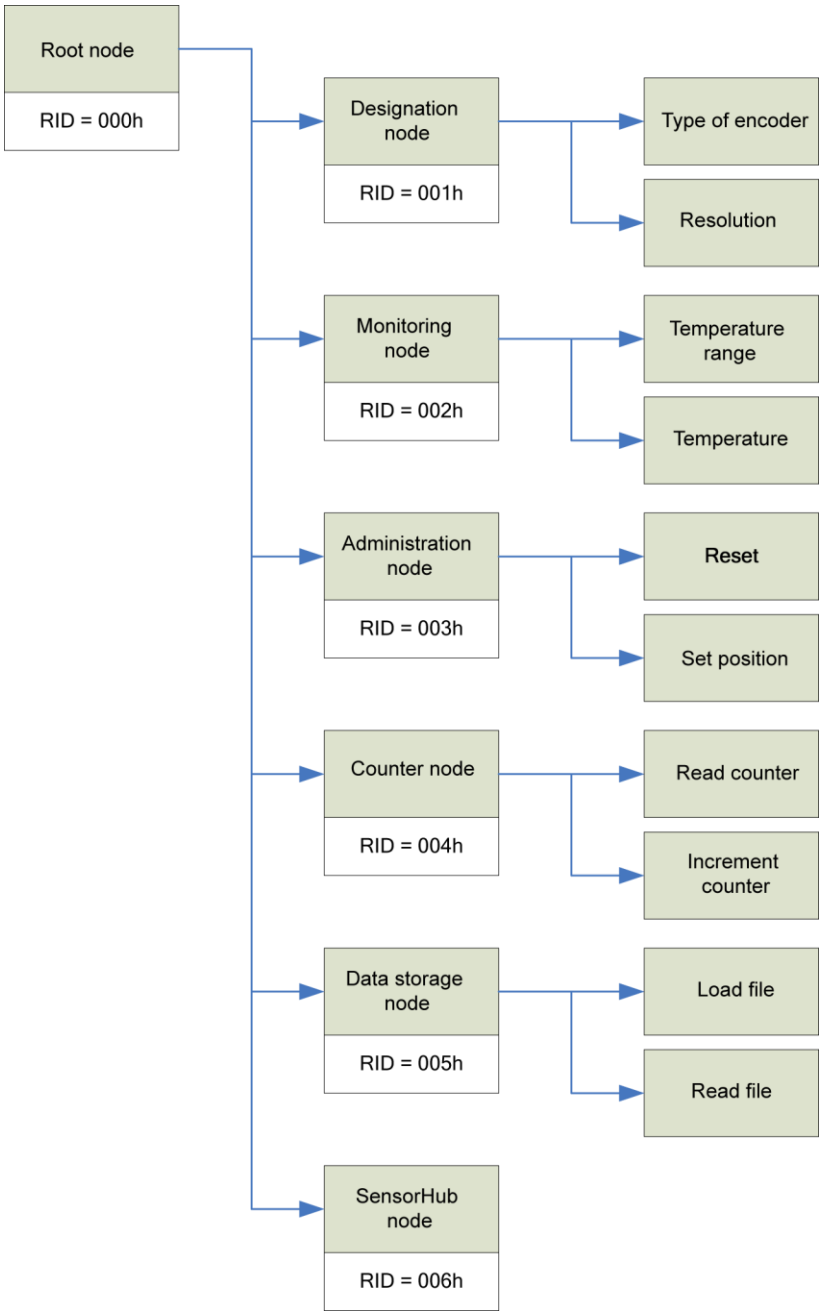


Figure 38: Tree structure of the resources database

The characteristics of a "long message" for reading a linked node are listed in Table 49.

Characteristic	Value	Description
DATA	-	-
R/W	1	Read
O/N	1	Offset
D/I	1	Indirect
LEN	1	2 bytes
ADD	Variable	Calling node
OFF ADD	Variable	Ordinal number of the linked node

Table 49: Parameters for node access.

The value stored in **OFF ADD** shows the ordinal number of the linked node, the resource identification of which should be returned. The ordinal number is given in the following list of all resources.

The result of this "long message" transaction is the resource index (RID) of the resource requested.

The resources data is described in detail in the resources list (see section 7.1.3).

7.1.3. Direct access

The defining values of a resource can be read from the DSL encoder by direct access (see section 6.6.2).

These defining values consist of a readable description of the resource (max. 8 characters), the data length, the access rights, a value for time overrun and the data type of the resource.

The desired value is selected by the user by setting a corresponding offset address.

A "long message" that uses direct access always has a time overrun of **75** ms.

Table 50 below sets out all possible access methods (direct and indirect) and associated values.

Resource type (see section 7.2)	Access	Offset address	Data	Note
Node	Direct reading	0/none	Resource name	e.g. "ROOT"
		1	Resource data length	e.g. 05h for 5 Sub-entries
		2	Read access level	e.g. 0 for access level 0
		3	Write access level	e.g. 2 for access level 2
		4	Time overrun	e.g. 46h for 70 ms
		5	Data type	00h for node indicator
	Indirect reading	0	Number of linked nodes	e.g. 5
		1	RID of the 1st linked node	e.g. 001h
		…		
All remaining	Direct reading	0/none	Resource name	e.g. “ENCTYPE”
		1	Resource data length	e.g. 02h for 2 bytes
		2	Read access level	e.g. 0 for access level 0
		3	Write access level	e.g. 2 for access level 2
		4	Time overrun	e.g. 46h for 70 ms
		5	Data type	e.g. 04h for 16 bits, unsigned
	Indirect read/write	Variable	Resource value	See section 7.2

Table 50: Different methods of resource access.

It should be noted that individual device families of the DSL motor feedback systems can contain different resources. The list of available resources is published in the device data sheet.

It should be noted that the defining values of the resources that have been laid down in a motor feedback system have priority over the values published in this manual.

7.2. Resources list

This section contains all the resources installed in a DSL motor feedback system.

It should be noted that the motor feedback system position and rotation speed values are process values and access to these values is different from access to general resources (see sections 6.3 and 6.4).

All resources are indicated using the "long message" characteristics that are valid for access (see section 6.6.2).

In addition, the definitions from the resources database (RDB) for each resource are described. These definitions are used to indicate the following resource properties:

RDB definition	Data area	Description
RID	0 – 1023 000h to 3FFh	Resources index: Is used as an address characteristic in a "long message".
Size	0 – 32767 0 to 7FFFh	Length of the resources data in bytes. Defines the area that can be used when accessing offset basis in a "long message".
R	 0 1 2 3 4 15	Read access: Read possible for all. For read, the "operator" access level is required. For read, the "maintenance" access level is required. For read, the "authorized client" access level is required. For read, the "service" access level is required. No read access possible.
W	 0 1 2 3 4 15	Write access: Write possible for all. For write, the "operator" access level is required. For write, the "maintenance" access level is required. For write, the "authorized client" access level is required. For write, the "service" access level is required. No write access possible.
Time overrun	0 – 254 255	Resources access time overrun in milliseconds. If the DSL system does not react to a "long message" within this period, then there is probably a processing error (see section 6.7.4). The resource needs more than 254 ms for processing or the time overrun is not deterministic.
Resource data type	00h 01h 02h 03h 04h 05h 06h 07h 08h 09h 0Ah 0Bh 10h to 4Fh	Node indicator (index, 16 bit) Void (no data) Bit (1 = true/0 = false) 8 bit, unsigned 16 bit, unsigned 32 bit, unsigned 64 bit, unsigned 8 bit, with sign 16 bit, with sign 32 bit, with sign 64 bit, with sign String (character chain) Data structure with data length 0 to 63 bytes

Table 51: Definitions of the resources database.

If the size of a resource gives a higher byte total than the data type needs, then it is an array of the data type given.

7.2.1. Node

All resources of a DSL motor feedback system have a logical tree structure (see section 7.1.2). This arrangement is structured with node resources.

An indirect read access to a node returns the address of a linked node or a linked resource. For this, an offset must be given to determine the type of information:

Offset	Value
0	Number of linked nodes *n*
1	RID of the first linked node
…	
n	RID of the *n*-th linked node

Table 52: Indirect read access to nodes.

7.2.1.1. Root node

The root node is the uppermost resource of the tree structure for the address (RID) 000h.

All nodes representing different resource groups are accessible from the root node.

Direct read access to the root node returns the defining values:

Defining value	Offset	Value
RID		000h
Resource name	0	"ROOT"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 53: Root node defining values.

Indirect read access to root nodes returns information on linked nodes (see Table 52).

7.2.1.2. Designation node

The designation node contains indicators to all resources associated with designations in the motor feedback system ("electronic type label").

Direct read access to the designation node returns the defining values:

Defining value	Offset	Value
RID		001h
Resource name	0	"IDENT"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 54: Designation node defining values.

Indirect read access to the designation node returns information on linked nodes (see Table 52).

7.2.1.3. Monitoring node

The monitoring node contains indicators to all resources associated with monitoring in the motor feedback system (e.g. temperature control).

Direct read access to the monitoring node returns the defining values:

Defining value	Offset	Value
RID		002h
Resource name	0	"MONITOR"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 55: Monitoring node defining values.

Indirect read access to the monitoring node returns information on linked nodes (see Table 52).

7.2.1.4. Administration node

The administration node contains indicators to all resources associated with administration in the motor feedback system (e.g. reset, determining access level).

Direct read access to the administration node returns the defining values:

Defining value	Offset	Value
RID		003h
Resource name	0	"ADMIN"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 56: Administration node defining values.

Indirect read access to the administration node returns information on linked nodes (see Table 52).

7.2.1.5. Counter node

The counter node contains indicators to all resources associated with the user-defined counter.

Direct read access to the counter node returns the defining values:

Defining value	Offset	Value
RID		004h
Resource name	0	"COUNTER"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 57: Counter node defining values.

Indirect read access to the counter node returns information on linked nodes (see Table 52).

7.2.1.6. Data storage node

The data storage node contains indicators to all resources associated with the user defined data storage.

Direct read access to the data storage node returns the defining values:

Defining value	Offset	Value
RID		005h
Resource name	0	"DATA"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 58: Data storage node defining values.

Indirect read access to the data storage node returns information on linked nodes (see Table 52).

7.2.1.7. SensorHub node

The SensorHub node contains indicators to all resources associated with the identification and actuation of external sensors.

Direct read access to the SensorHub node returns the defining values:

Defining value	Offset	Value
RID		006h
Resource name	0	"SENSHUB"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	75
Data type	5	00h – node indicator

Table 59: Data storage node defining values.

Indirect read access to the SensorHub node returns information on linked nodes (see Table 52).

7.2.2. Designation resources

The designation resources of the DSL motor feedback system contain the encoder electronic type label.

7.2.2.1. Type of encoder

The type of encoder describes the basic functionality of the motor feedback system.

Direct read access to the type of encoder returns the defining values:

Defining value	Offset	Value
RID		080h
Resource name	0	"ENCTYPE"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 60: Defining values for type of encoder.

The following table contains the possible values for the type of encoder and their meaning.

Value (dec.)	Value (hex.)	Type of encoder
0	00 00h	Rotary encoder, bipolar counting
1	00 01h	Linear encoder, bipolar counting
2	00 02h	Rotary encoder, unipolar counting
3	00 03h	Linear encoder, unipolar counting

Table 61: Definition of the type of encoder.

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	80	00	00	01
Wait for FREL = 1													
Read	Type of encoder												

Table 62: Read type of encoder.

7.2.2.2. Resolution

The resolution value defines the number of steps per rotation of the encoder (rotary encoder) or the length of a measurement step in multiples of 1 nm (linear encoder).

Direct read access to resolution returns the defining values:

Defining value	Offset	Value
RID		081h
Resource name	0	"RESOLUTN"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	05h – 32 bit, unsigned

Table 63: Resolution defining values.

The resolution value is given as a 32 bit unsigned value.

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									58	81	00	00	01
Wait for FREL = 1													
Read	Resolution (32 bit)												

Table 64: Reading the resolution.

7.2.2.3. Measurement range

The measurement range defines the number of coded rotations of the encoder (rotary encoders), or the coded measurement range in multiples of measurement steps (linear encoders).

Direct read access to measurement range returns the defining values:

Defining value	Offset	Value
RID		082h
Resource name	0	"RANGE"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	05h – 32 bit, unsigned

Table 65: Resolution defining values.

The measurement range is given as a 32 bit unsigned value.

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									78	82	00	00	01
Wait for FREL = 1													
Read	Measurement range (32 bit)												

Table 66: Reading the measurement range.

7.2.2.4. Type name

This resource indicates the type name of the encoder. The designation is stored in ASCII format with a maximum length of 18 characters. Unallocated characters are stored with the ASCII code 00h.

Direct read access to type name returns the defining values:

Defining value	Offset	Value
RID		083h
Resource name	0	"TYPECODE"
Data size	1	18
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	0Bh - string

Table 67: Type name defining values.

It should be noted that to read the whole code designation requires up to three "long message" transactions, as a "long message" can only contain 8 bytes of data.

When accessing offset basis, the OFF ADD characteristic gives the first character of the type name to be returned in the "long message".

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7C	83	00	00	01
Wait for FREL = 1													
Read	Characters 1 to 8 of the type name												
Write									7C	83	00	08	01
Wait for FREL = 1													
Read	Characters 9 to 16 of the type name												
Write									74	83	00	10	01
Wait for FREL = 1													
Read	Characters 17 to 18 of the type name												

Table 68: Read type name.

7.2.2.5. Serial number

This resource indicates the serial number of the encoder. The serial number is stored in ASCII format with a maximum length of 10 characters. Unallocated characters are stored with the ASCII code 00h.

Direct read access to serial number returns the defining values:

Defining value	Offset	Value
RID		084h
Resource name	0	"SERIALNO"
Data size	1	10
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	0Bh - string

Table 69: Serial number defining values.

It should be noted that to read the whole serial number requires up to two "long message" transactions, as a "long message" can only contain 8 bytes of data.

When accessing offset basis, the OFF ADD characteristic gives the first character of the serial number to be returned in the "long message".

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7C	84	00	00	01
Wait for FREL = 1													
Read	Characters 1 to 8 of the serial number												
Write									74	84	00	08	01
Wait for FREL = 1													
Read	Characters 9 to 10 of the serial number												

Table 70: Reading the serial number.

7.2.2.6. Device version

This resource indicates the firmware and hardware version of the encoder. The firmware version is stored in ASCII format with a maximum length of 16 characters, the hardware version is in the same format with a maximum of 4 characters. Unallocated characters are stored with the ASCII code 00h.

Direct read access to device version returns the defining values:

Defining value	Offset	Value
RID		085h
Resource name	0	"FWREVNO"
Data size	1	20
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	0Bh - string

Table 71: Device version defining values.

It should be noted that to read the whole device version data requires up to three "long message" transactions, as a "long message" can only contain 8 bytes of data.

When accessing offset basis, the OFF ADD characteristic gives the first character of the device version to be returned in the "long message".

The device version is given in the following format:

Byte	Description
0 to 15	ASCII characters of the firmware version
16 to 19	ASCII characters of the hardware version

Table 72: Definition of the device version.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7C	85	00	00	01
Wait for FREL = 1													
Read	Characters 1 to 8 of the firmware version												
Write									7C	85	00	08	01
Wait for FREL = 1													
Read	Characters 9 to 16 of the firmware version												
Write									78	85	00	10	01
Wait for FREL = 1													
Read	Characters 1 to 4 of the hardware version												

Table 73: Reading the device version.

7.2.2.7. Firmware date

This resource indicates the firmware date of the encoder. The firmware date is stored in ASCII format with a maximum length of 8 characters.

Direct read access to firmware date returns the defining values:

Defining value	Offset	Value
RID		086h
Resource name	0	"FWDATE"
Data size	1	8
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	0Bh - string

Table 74: Firmware date defining values.

The firmware date is given in the following format:

Byte	Value	Description
7/6	'00' to '99'	Firmware date year, i.e 20yy
5	'.'	Decimal point as separator
4/3	'01' to '12'	Firmware date month
2	'.'	Decimal point as separator
1/0	'01' to '31'	Firmware date day

Table 75: Firmware date definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									5C	86	00	00	01
Wait for FREL = 1													
Read	Firmware date "DD.MM.YY"												

Table 76: Reading the firmware date.

7.2.2.8. EEPROM size

This resource indicates the total size of the non-volatile memory in the encoder available for storage of user data. The size of the EEPROM is given as an unsigned 16 bit value, which shows the number of bytes.

Direct read access to the EEPROM size returns the defining values:

Defining value	Offset	Value
RID		087h
Resource name	0	"EESIZE"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 77: EEPROM size defining values.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	87	00	00	01
Wait for FREL = 1													
Read	EEPROM size												

Table 78: Reading the EEPROM size.

7.2.3. Monitoring resources

The DSL motor feedback system monitoring resources indicate the current ambient values and their range limits as well as usage statistics and an error stack.

7.2.3.1. Temperature range

This resource indicates the minimum and maximum permitted values for the temperature of the DSL motor feedback system given in the product data sheet.

Direct read access to temperature range returns the defining values:

Defining value	Offset	Value
RID		0C0h
Resource name	0	"TEMPRNG"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	08h – 16 bit, with sign

Table 79: Temperature range defining values.

The temperature range values are stored as signed 16 bit values in the form of two's complements. The temperature value units are tenths of degrees Celsius (0.1 °C).

Examples of temperature range values:

Temperature	Resource value (bin.)	Resource value (hex.)
20.0 °C	0000 0000 1100 1000b	00C8h
115.0 °C	0000 0100 0111 1110b	047Eh
-40.0 °C	1111 1110 0111 0000b	FE70h

Table 80: Examples of temperature ranges.

The temperature range values are given in the following format:

Byte	Value	Description
3/2	-2730 to 10000	Maximum permitted encoder temperature in 0.1 °C
1/0	-2730 to 10000	Minimum permitted encoder temperature in 0.1 °C

Table 81: Temperature range definition.

By accessing offset basis, only one of two temperature range values can be given.

Offset value	Length of the message	Return values
0000h	4	Temperature range minimum and maximum values
0000h	2	Minimum temperature
0002h	2	Maximum temperature

Table 82: Selection of the temperature range offset.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									58	C0	00	00	01
Wait for FREL = 1													
Read	Min. temp.		Max. temp.										

Table 83: Reading the temperature range.

7.2.3.2. Temperature

This resource indicates the current temperature of the DSL motor feedback system.

The temperature is measured once per second.

If this relates to the temperature of the DSL motor feedback system, an error is indicated if the measured value is outside one or other of the range limits (see section 6.7.4, error group 3, error number 0).

Direct read access to temperature returns the defining values:

Defining value	Offset	Value
RID		0C1h
Resource name	0	"TEMPRTUR"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	08h – 16 bit, with sign

Table 84: Temperature defining values.

The temperature value is stored as a signed 16 bit two's complement. The temperature value units are tenths of degrees Celsius (0.1 °C).The temperature value is given in the following format:

Byte	Value	Description
1/0	-2730 to 10000	Current temperature value in 0.1 °C

Table 85: Temperature definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									74	C1	00	00	01
Wait for FREL = 1													
Read	Encoder temperature												

Table 86: Reading the encoder temperature.

7.2.3.3. LED current range

This resource indicates the minimum and maximum permitted values for the LED current values of the optical DSL motor feedback system given in the product data sheet.

Direct read access to LED current range returns the defining values:

Defining value	Offset	Value
RID		0C2h
Resource name	0	"LEDRANGE"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 87: LED current range defining values.

The values of the LED current range are stored as unsigned 16 bit values. The LED current value units are tenths of a milliampere (0.1mA).

Examples of LED current values:

Current	Resource value (bin.)	Resource value (hex.)
5 mA	0000 0000 0011 0010b	0032h
20 mA	0000 0000 1100 1000b	00C8h

Table 88: Examples of LED current range.

The values for the LED current range are given in the following format:

Byte	Value	Description
3/2	0 to 65535	Maximum permitted encoder LED current in 0.1 mA
1/0	0 to 65535	Minimum permitted encoder LED current in 0.1 mA

Table 89: LED current range definition.

By accessing offset basis, only one of two LED current range values can be given.

Offset value	Length of the message	Return values
0000h	4	LED current minimum and maximum values
0000h	2	Minimum LED current
0002h	2	Maximum LED current

Table 90: Offset selection for the LED current range.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									58	C2	00	00	01
Wait for FREL = 1													
Read	Min. current		Max. current										

Table 91: Reading the LED current range.

7.2.3.4. LED current

This resource indicates the LED current of an optical DSL motor feedback system.

The LED current is measured once per second.

If the measured LED current is near the upper range limit, it is possible that the end of the product life is near.

If the measured LED current is outside either one of the range limits, an error is indicated (see section 6.7.4, error group 3, error number 1).

Direct read access to LED current returns the defining values:

Defining value	Offset	Value
RID		0C3h
Resource name	0	"LEDCURR"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 92: LED current defining values.

The value of the LED current is stored as an unsigned 16 bit value. The LED current value units are tenths of a milliampere (0.1mA).

The LED current value is given in the following format:

Byte	Value	Description
1/0	0 to 65535	Encoder LED current in 0.1 mA

Table 93: LED current definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	C3	00	00	01
Wait for FREL = 1													
Read	LED current												

Table 94: Reading the LED current.

7.2.3.5. Supply voltage range

This resource indicates the minimum and maximum permitted values for the internal supply voltage for the DSL motor feedback system given in the product data sheet.

Direct read access to supply voltage range returns the defining values:

Defining value	Offset	Value
RID		0C4h
Resource name	0	"SUPRANGE"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 95: Supply voltage range defining values.

The values of the supply voltage range are stored as unsigned 16 bit values. The supply voltage units are 1 mV.

The values for the supply voltage range are given in the following format:

Byte	Value	Description
3/2	0 to 65535	Maximum permitted internal supply voltage for the encoder in mV
1/0	0 to 65535	Minimum permitted internal supply voltage for the encoder in mV

Table 96: Supply voltage range definition.

By accessing offset basis, only one of two supply voltage range values can be given.

Offset value	Length of the message	Return values
0000h	4	Minimum and maximum value of the supply voltage
0000h	2	Minimum supply voltage
0002h	2	Maximum supply voltage

Table 97: Offset selection for the supply voltage range.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									58	C4	00	00	01
Wait for FREL = 1													
Read	Min. voltage		Max. voltage										

Table 98: Reading the supply voltage range.

7.2.3.6. Supply voltage

This resource indicates the supply voltage of a DSL motor feedback system.

The supply voltage is measured every 10 msec.

If the measured shaft rotation speed is outside either one of the range limits, an error is indicated (see section 6.7.4, error group 3, error number 2).

Direct read access to supply voltage returns the defining values:

Defining value	Offset	Value
RID		0C5h
Resource name	0	"SUPVOLT"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 99: Supply voltage defining values.

The value of the supply voltage is stored as an unsigned 16 bit value. The supply voltage units are 1 mV.

The supply voltage value is given in the following format:

Byte	Value	Description
1/0	0 to 65535	Current encoder supply voltage in mV

Table 100: Supply voltage definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									58	C4	00	00	01
Wait for FREL = 1													
Read	Supply voltage												

Table 101: Reading the supply voltage.

7.2.3.7. Rotation speed range

This resource indicates the permitted maximum shaft rotation speed for rotary DSL motor feedback systems given in the product data sheet.

Direct read access to rotation speed range returns the defining values:

Defining value	Offset	Value
RID		0C6h
Resource name	0	"SPEEDRNG"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 102: Rotation speed range defining values.

The rotation speed range value is stored as a 16 bit unsigned value. The rotation speed value units are 1 rotation per minute (min^{-1}).

It should be noted that the current rotation speed value is given as a process value in the "horizontal channel" (see section 6.3).

The rotation speed range value is given in the following format:

Byte	Value	Description
1/0	0 to 65535	Maximum permitted rotation speed of the encoder in min^{-1}

Table 103: Rotation speed range definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	C6	00	00	01
Wait for FREL = 1													
Read	Max. rotation speed												

Table 104: Reading the rotation speed range.

7.2.3.8. Rotation speed

This resource indicates the shaft rotation speed of a rotary DSL motor feedback system.

The rotation speed is measured once per second.

If the measured shaft rotation speed is outside either one of the range limits, an error is indicated (see section 6.7.4, error group 3, error number 3).

Direct read access to rotation speed returns the defining values:

Defining value	Offset	Value
RID		0C7h
Resource name	0	"SPEED"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 105: Rotation speed defining values.

The rotation speed value is stored as a 16 bit unsigned value. The rotation speed value units are 1 rotation per minute (min^{-1}).

It should be noted that the rotation speed value is given synchronously with the DSL measurements trigger signal as a process value in the "horizontal channel" (see section 6.3).

The rotation speed value is given in the following format:

Byte	Value	Description
1/0	0 to 65535	Current rotation speed of the encoder in min^{-1}

Table 106: Rotation speed definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	C7	00	00	01
Wait for FREL = 1													
Read	Rotation speed												

Table 107: Reading the rotation speed.

7.2.3.9. Acceleration range

This resource indicates the permitted minimum and maximum shaft acceleration for rotary DSL motor feedback systems given in the product data sheet.

Direct read access to acceleration range returns the defining values:

Defining value	Offset	Value
RID		0C8h
Resource name	0	"ACCRANGE"
Data size	1	2
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	04h – 16 Bit, unsigned

Table 108: Acceleration range defining values.

The value of the acceleration range is stored as an unsigned 16 bit value. The acceleration value units are 1000 rad/s².

It should be noted that the current acceleration value can be derived from the rotation speed process value in the "horizontal channel" (see section 6.3).

The acceleration range value is given in the following format:

Byte	Value	Description
1/0	0 to 65535	Maximum permitted rotational acceleration of the encoder in 1000 rad/s²

Table 109: Acceleration range definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									54	C8	00	00	01
Wait for FREL = 1													
Read	Max. acceleration												

Table 110: Reading the acceleration range.

7.2.3.10. Lifetime

This resource indicates the operating time and the observed number of shaft rotations for a DSL motor feedback system. For safety variants, the remaining encoder task lifetime is also indicated.

Direct read access to lifetime returns the defining values:

Defining value	Offset	Value
RID		0CBh
Resource name	0	"LIFETIME"
Data size	1	8 (12 for safety variants)
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	05h – 32 bit, unsigned

Table 111: Lifetime defining values.

The number of shaft rotations of the product is determined based on an average rotation speed. The integration time lasts one second.

The values for operating time, remaining task lifetime and number of shaft rotations are all stored as unsigned 32- bit values. The operating time units and the remaining task lifetime are 1 minute. The values are stored every 20 minutes in a non-volatile memory.

CAUTION

If the remaining task lifetime falls to 0, the encoder continuously issues error message 22 (safety error). If this is the case, the encoder must be replaced.

Examples of time values:

Duration	Resource value (bin.)	Resource value (hex.)
10 min	0000 0000 0000 0000 0000 0000 0000 1010b	0000 000Ah
200 hours	0000 0000 0000 0000 0010 1110 1110 0000b	0000 2EE0h
5 years	0000 0000 0010 1000 0001 1001 1010 0000b	0028 19A0h

Table 112: Examples of lifetime.

The lifetime values are given in the following format:

Byte	Value	Description
11 to 8	0 to 4294967295	Remaining task lifetime in minutes
7 to 4	0 to 4294967295	Number of shaft rotations
3 to 0	0 to 4294967295	Operating time in minutes

Table 113: Lifetime definition.

By accessing offset basis, only one of the lifetime values can be given.

Offset value	Length of the message	Return values
0000h	4	Operating time
0004h	4	Number of shaft rotations
0008h	4	Remaining task lifetime

Table 114: Selection of the lifetime offset.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7C	CB	00	00	01
Wait for FREL = 1													
Read	Operating time				Number of shaft rotations								

Table 115: Reading the lifetime.

7.2.3.11. Error protocol

This resource returns stored DSL motor feedback system error messages.

Direct read access to error protocol returns the defining values:

Defining value	Offset	Value
RID		0CCh
Resource name	0	"ERRORLOG"
Data size	1	16 per error protocol entry
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	20h – structure with 16 bytes

Table 116: Error protocol defining values.

As soon as the encoder identifies an error, this error is indicated to the frequency inverter application (see section 6.5). In addition, errors are stored in the non-volatile memory of the DSL motor feedback system.

In addition, those errors identified when the establishment of a connection to the frequency inverter application failed are also stored in the error protocol. This resource provides an overview of these errors.

A DSL motor feedback system can store a set number of errors in its error protocol. If the total of errors recorded exceeds this number, the oldest entries are overwritten. The maximum number of error protocol entries can be found in the product data sheet.

All errors are recorded with time information, and several process and condition values from the time at which the error occurred.

Error protocol entries are each stored in 16 bytes.

The values for the error protocol are given in the following format:

Byte	Value	Description
15	00 to FFh	Error code (see section 6.7.4)
14	-	Reserved
13/12	0 to 65535	Acceleration in 1000 rad/s² during the error
11/10	0 to 65535	Rotation speed in min^{-1} during the error
9/8	0 to 65535	Internal supply voltage in mV during the error
7/6	0 to 65535	LED current in 0.1 mA during the error
5/4	-2730 to 10000	Temperature in 0.1 °C during the error
3 to 0	0 to 4294967295	Error time information (operating time or real-time stamp)

Table 117: Error protocol entries definition.

All error protocol entries are stored sequentially and are accessible by giving the individual values for the offset address.

To give a complete error entry, two "long message" transactions must be carried out as a message can only contain 8 bytes.

It should be noted that the highest offset address that can be given depends on the maximum number of error protocol entries for the particular product.

Offset value	Length of the message	Return values
00 00h	8	Number of stored error messages
00 01h	8	First part of the most recently occurring error
01 01h	8	Second part of the most recently occurring error
00 02h	8	First part of the error protocol entry no. 2
01 02h	8	Second part of the error protocol entry no. 2
…	8	…
00 xxh	8	First part of the oldest error protocol entry
01 xxh	8	Second part of the oldest error protocol entry

Table 118: Offset selection for the error protocol.

The higher value offset byte indicates whether the first part of the error message (00h) or the second part (01h) will be given.

The lower value offset byte indicates the desired error number.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7C	CC	00	01	01
Wait for FREL = 1													
Read	Bytes 0 - 7 of the error protocol entry #1												
Write									7C	CC	01	01	01
Wait for FREL = 1													
Read	Bytes 8 - 15 of the error protocol entry #1												

Table 119: Reading the error protocol entries.

7.2.3.12. Usage histogram

This resource gives histogram values of encoder parameters. The histogram values indicate how often a parameter value was measured during the lifetime of the encoder.

Direct read access to usage histogram returns the defining values:

Defining value	Offset	Value
RID		0CDh
Resource name	0	"USAGEHIS"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	20h – structure with 16 bytes

Table 120: Usage histogram defining values.

Recorded encoder parameters are measured at one minute intervals and stored every 20 minutes in a non-volatile memory.

The following table contains the encoder parameters that can be recorded in a histogram and stored. In addition, the range limits and the resolution of the histogram are given.

Encoder parameters	Min. class	Max. class	Width of histogram class
Temperature	< -40 °C	>= 120 °C	10 °C
LED current	0 to 5 mA	>= 50 mA	5 mA
Supply voltage	< 6.0 V	>= 14.0 V	1.0 V
Rotation speed	0 to 500 min^{-1}	>= 10,000 min^{-1}	500 min^{-1}

Table 121: Encoder parameter histograms definitions.

The values of the usage histograms are each stored in 4 bytes.

The values for the usage histograms are given in the following format:

Byte	Value	Description
3/2/1	00 00 00h - FF FF FFh	Number of parameter values in the histogram class
0	00h - FFh	Identification of histogram class

Table 122: Value definitions in usage histograms.

The identification of the histogram class is transmitted in the offset value with an identification for the requested encoder parameter. The identification of the histogram class depends on the encoder parameter selected (see the following table).

Encoder parameters	Histogram class	Identification of histogram class
Temperature	< -40 °C	00h
	-40 to -30 °C	01h
	-30 to -20 °C	02h
	-20 to -10 °C	03h
	-10 to 0 °C	04h
	0 to 10 °C	05h
	10 to 20 °C	06h
	20 to 30 °C	07h
	30 to 40 °C	08h
	40 to 50 °C	09h
	50 to 60 °C	0Ah
	60 to 70 °C	0Bh
	70 to 80 °C	0Ch
	80 to 90 °C	0Dh
	90 to 100 °C	0Eh
	100 to 110 °C	0Fh
	110 to 120 °C	10h
	>= 120 °C	11h
LED current	0 to 5 mA	00h
	5 to 10 mA	01h
	10 to 15 mA	02h
	15 to 20 mA	03h
	20 to 25 mA	04h
	25 to 30 mA	05h
	30 to 35 mA	06h
	35 to 40 mA	07h
	40 to 45 mA	08h
	45 to 50 mA	09h
	> 50 mA	0Ah
Supply voltage	< 6.0 V	00h
	6.0 to 7.0 V	01h
	7.0 to 8.0 V	02h
	8.0 to 9.0 V	03h
	9.0 to 10.0 V	04h
	10.0 to 11.0 V	05h
	11.0 to 12.0 V	06h
	12.0 to 13.0 V	07h
	13.0 to 14.0 V	08h
	> 14.0 V	09h

Rotation speed	0 to 500 min^{-1}	00h
	500 to 1000 min^{-1}	01h
	1000 to 1500 min^{-1}	02h
	1500 to 2000 min^{-1}	03h
	2000 to 2500 min^{-1}	04h
	2500 to 3000 min^{-1}	05h
	3000 to 3500 min^{-1}	06h
	3500 to 4000 min^{-1}	07h
	4000 to 4500 min^{-1}	08h
	4500 to 5000 min^{-1}	09h
	5000 to 5500 min^{-1}	0Ah
	5500 to 6000 min^{-1}	0Bh
	6000 to 6500 min^{-1}	0Ch
	6500 to 7000 min^{-1}	0Dh
	7000 to 7500 min^{-1}	0Eh
	7500 to 8000 min^{-1}	0Fh
	8000 to 8500 min^{-1}	10h
	8500 to 9000 min^{-1}	11h
	9000 to 9500 min^{-1}	12h
	9500 to 10,000 min^{-1}	13h
	> 10,000 min^{-1}	14h

Table 123: Histogram classes.

The offset value must be given in the following format:

Bits	Value	Definition
0 to 7	00h to FFh	Identification of histogram class
8 to 11	0h 1h 2h 3h	Request temperature Request LED current Request supply voltage Request rotation speed

Table 124: Selection of the histogram offset.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									78	CD	00	07	01
Wait for FREL = 1													
Read	07	Number of measurements 20 to 30°C											
Write									78	CD	03	04	01
Wait for FREL = 1													
Read	04	Number of measurements 2000 to 2500 rpm											

Table 125: Reading histogram entries.

7.2.4. Administration resources

The administration resources of the DSL motor feedback system provide access to the encoder options settings.

7.2.4.1. Reset/shut-down

A write access to this resource causes a reset or a shut-down of the DSL motor feedback system.

Direct read access to reset returns the defining values:

Defining value	Offset	Value
RID		100h
Resource name	0	"RESET"
Data size	1	0
Read access level	2	15
Write access level	3	0
Time overrun	4	150
Data type	5	01h - empty

Table 126: Reset defining values.

The effect of a reset is that the encoder is initialized in the same way as at switch-on (see section 6.1). Following a reset command, no report is returned.

It should be noted that allowance must be made for the initializing time of the encoder as well as the maximum time overrun.

Shutting down causes the encoder to discontinue all communication.

It should be noted that after shut-down, the encoder no longer reacts to any command until it has been switched off and on again.

The offset value allows selection of the desired function (reset or shut-down):

Value	Definition
0 (or less)	Motor feedback system reset
1	Motor feedback system shut-down

Table 127: Function selection.

Before carrying out a reset or shut-down, all relevant data in the EEPROM is stored. This affects lifetime data and the usage histogram.

It should be noted that the shut-down function can be used to reliably store all lifetime data before a planned shut-down.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									11	00	00	00	01
Wait for FREL = 1													

Table 128: Reset write command.

7.2.4.2. Set position

Using this resource, an arbitrary position value can be allocated to the current mechanical shaft position and the current position offset can be read.

With synchronous servo drives, the position information is used for motor commutation. The incorrect use of this resource can adversely affect the motor. This function should only be called up by the motor manufacturers.

Direct read access to set position returns the defining values:

Defining value	Offset	Value
RID		101h
Resource name	0	"SETPOS"
Data size	1	8
Read access level	2	0
Write access level	3	2
Time overrun	4	100
Data type	5	06h – 64 bit, unsigned

Table 129: Set position defining values.

There is no synchronization for movements in progress. This function may only be used when the encoder shaft is stationary.

During a write access, the current position is set for the transmitted value. The position value to be allocated to the current shaft position is transmitted as an unsigned 40 bit value. Only values in the measurement range of the DSL motor feedback system are valid. During a read access, the offset value currently being used is transmitted in the same format.

The position value for this command must be given in the following format:

Byte	Value	Description
4 to 0	00 0000 0000 to FF FFFF FFFFh	New position value for the current mechanical shaft position. The position value is right justified.

Table 130: Set position definition.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	Byte 0 to 4 of the target position					00	00	00	1D	01	00	00	01
Wait for FREL = 1													

Table 131: Set write command position.

An encoder protocol reset is carried out after this has been done.

7.2.4.3. Set access level

This resource is used to set or read the encoder access level. The access level determines which functions are accessible for the user application. The access level required for each function is set out in the resources list (section 7.2).

Direct read access to Set access level returns the defining values:

Defining value	Offset	Value
RID		104h
Resource name	0	"SETACCESS"
Data size	1	8
Read access level	2	0
Write access level	3	0
Time overrun	4	70
Data type	5	18h – structure with 8 bytes

Table 132: Set access level defining values.

After switch-on or after a reset, the access level is always set to "0", i.e. to the lowest (public) access rights.

To alter the access level, the corresponding access key must be transmitted to the DSL encoder. The access level is retained until another level is set using this resource.

The table below sets out the access levels and the standard access keys available with which the appropriate level can be set.

Access level	Standard access key	Usage
0	No access key necessary	Publicly accessible system functions
1	31 31 31 31h	Protected system functions - "operator" level
2	32 32 32 32h	Protected system functions - "maintenance" level
3	33 33 33 33h	Protected system functions - "authorized client" level
4	34 34 34 34h	Protected system functions - "service" level

Table 133: Access levels and standard access keys.

The access level is given in the following format:

Byte	Value	Description
7/6/5/4	0000 0000 to FFFF FFFFh	Access keys for the requested access level
3/2/1		Reserved for later use
0	00h to 04h	Requested access level

Table 134: Set access level definition.

The currently set access level can be determined using a read access. This access level is returned in byte 0 of the long message.

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	01	00	00	00	31	31	31	31	1D	04	00	00	01
Wait for FREL = 1													

Table 135: Set access level (in this example: 01h with access key 31313131h).

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									55	04	00	00	01
Wait for FREL = 1													
Read	00	00											

Table 136: Reading the current access level (in this example: 00h).

7.2.4.4. Change access key

This resource is used to change the access key required to set the appropriate access level. The access level determines which functions are accessible for the user application. The access level required for each function is set out in the resources list (section 7.2).

Direct read access to change access key returns the defining values:

Defining value	Offset	Value
RID		105h
Resource name	0	"CHNGKEY"
Data size	1	8
Read access level	2	15
Write access level	3	0
Time overrun	4	90
Data type	5	18h – structure with 8 bytes

Table 137: Change access key defining values.

To change the access key, both the old and the new access keys for the target access level as well as the access level itself must be transmitted to the DSL encoder.

It should be noted that the access key for any level can be changed irrespective of the access level currently selected.

The access key is changed when data in the following format is transmitted:

Byte	Value	Description
7/6/5/4	0000 0000 to FFFF FFFFh	Old access key
3/2/1/0	0000 0000 to FFFF FFFFh	New access key

Table 138: Change access key definition.

A read access to this resource is not possible.

The offset value indicates the target access level of the key change.

Offset value	Description
0 – 4	Target access level

Table 139: Selection of access level.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	12	34	56	78	31	31	31	31	3D	05	02	00	01
Wait for FREL = 1													

Table 140: Changing the access key (in this example for access level 02h, changing from 31313131h to 12345678h).

7.2.4.5. User-defined warnings

This resource allows the user to program warnings to be set when limit values are exceeded or there are bit changes to the DSL motor feedback system parameters.

All user-defined limit values or bit masks are checked once per second. The number of available user-defined warnings is set out in the product data sheet.

If a user-defined warning is triggered, this appears as a motor feedback system error message (see section 6.7.4) and is recorded in the error protocol (see section 7.2.3.11).

Direct read access to user-defined warnings returns the defining values:

Defining value	Offset	Value
RID		107h
Resource name	0	"UWARNING"
Data size	1	8
Read access level	2	0
Write access level	3	2
Time overrun	4	90
Data type	5	18h – structure with 8 bytes

Table 141: User-defined warnings defining values.

A user-defined warning is configured by selecting the offset value for configuring the warning (see below):

Byte	Value	Meaning
7/6/5/4		Reserved
3/2	0000 to FFFFh	Offset value of the monitored resource
0 (bit 1/0) / 1	000 to 3FFh	Resources index of the monitored resource
0 (bit 7/6/5)	 0 1 2 3 4 5 to 7	Type of warning: Warning switched off Warning if monitored resource below limit value Warning if monitored resource above limit value Warning if monitored resource bit is deleted Warning if monitored resource bit is set Reserved
0 (bit 4/3/2)	 0 1 2 3 4 5 6 7	Limit value data format: Not applicable 16 bit, unsigned 32 bit, unsigned 64 bit, unsigned Not applicable 16 bit, with sign 32 bit, with sign 64 bit, with sign

Table 142: User-defined warning configuration bits.

The limit value or the bit mask for the user-defined warning is set by selecting the offset value for limit values (see below) and transmitting the limit value in the following format:

Byte	Value	Meaning
7 to 0	Each	Limit value or bit mask for 64 bit value
3 to 0	Each	Limit value or bit mask for 32 bit value
1/0	Each	Limit value or bit mask for 16 bit value

Table 143: Setting value of user-defined warning.

Alternatively, the currently set values of a user-defined warning can be read in the same format.

The offset value indicates which user-defined warning is to be processed and whether the configuration bits or the value are affected.

Offset value	Meaning
00h	Configuration bits for user-defined warning 1
01h	Configuration bits for user-defined warning 2
…	
0Fh	Configuration bits for user-defined warning 16
10h	Limit value/bit mask for user-defined warning 1
11h	Limit value/bit mask for user-defined warning 2
…	
1Fh	Limit value/bit mask for user-defined warning 16

Table 144: User-defined warning offset value.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	34	C1	00	00	00	00	00	00	39	07	00	00	01
Wait for FREL = 1													
Transaction	**Register**												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	03	E8	00	00	00	00	00	00	39	07	00	10	01
Wait for FREL = 1													

Table 145: Writing a user-defined warning (here: switch on warning 1 if encoder temperature above 100 °C).

7.2.4.6. Factory settings

This resource allows all DSL motor feedback system user-defined settings to be reset to the factory settings.

The following values are reset by this command:

- Position offset (see section 7.2.4.2)
- Changed access key (see section 7.2.4.4)
- User-defined warnings (see section 7.2.4.5)
- Counter (see section 7.2.5.1)
- All user files (see section 7.2.6)
- User settings for SensorHub I/Os (see section 7.2.7.2)

The "factory settings" command deletes all user-defined settings and data. Use this function with care.

It should be noted that lifetime information, the error protocol and the usage histogram are not affected by this command.

Direct read access to factory settings returns the defining values:

Defining value	Offset	Value
RID		108h
Resource name	0	"FACRESET"
Data size	1	8
Read access level	2	15
Write access level	3	2
Time overrun	4	255
Data type	5	0Bh - string

Table 146: Factory settings defining values.

To revert to factory settings, a write command with specified code word must be sent to this resource.

Byte	Value	Meaning
0 to 7	"RESETALL"	Code word to revert to factory settings

Table 147: Factory settings definition.

A read access to this resource is not possible.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	52	45	53	45	54	41	4C	4C	1D	08	00	00	01
Wait for FREL = 1													

Table 148: Factory settings.

7.2.4.7. User-defined encoder index

This resource is used to set or read the user-defined encoder index. This index can be freely programmed by the user and is indicated when the encoder is switched on in the ENC_ID register (see section 5.3.10).

The user-defined encoder index can be used to distinguish between several DSL Master instances occurring in an FPGA. This is required for safety-related use.

Direct read access to user-defined encoder index returns the defining values:

Defining value	Offset	Value
RID		109h
Resource name	0	"ENCIDENT"
Data size	1	2
Read access level	2	0
Write access level	3	3
Time overrun	4	90
Data type	5	04h – 16 Bit, unsigned

Table 149: User-defined encoder index defining values.

The user-defined encoder index can be between 0 and 25. Inputting a higher value will cause an error message.

The user-defined encoder index is given in the following format:

Byte	Value	Description
7 to 2		Reserved for later use
1/0	0 to 15 Other values	Requested user-defined encoder index Reserved for later use

Table 150: User-defined encoder index definition.

A previously set user-defined encoder index can be identified using a read access. The default value is "0".

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									55	09	00	00	01
Wait for FREL = 1													
Read	00	00											

Table 151: Reading the current user-defined encoder index (in this example: 00h).

7.2.4.8. Position filter setting

This resource is used to adjust or read the DSL motor feedback system position filter setting. In each one of these systems there is a filter with a low pass characteristic that reduces the position value identification interference. Here, more effective filtering must be balanced against a consequent long delay to the signal that affects acceleration.

The position filter characteristic depends on individual encoder types and is specified in the related data sheet.

Direct read access to position filter setting returns the defining values:

Defining value	Offset	Value
RID		10Ah
Resource name	0	"POSFILT"
Data size	1	4
Read access level	2	0
Write access level	3	3
Time overrun	4	90
Data type	5	05h – 32 bit, unsigned

Table 152: Position filter setting defining values.

The position filter is set in the following format:

Byte	Value	Description
3 to 0	3000 to 37500	Mechanical filter limit frequency, measured in rotations per minute (rpm)

Table 153: Position filter definition.

A previously set position filter can be identified using a read access.

For this resource, access to the offset base is not meaningful as the size of the resource data is smaller than the maximum for a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									59	0A	00	00	01
Wait for FREL = 1													
Read	00	00	88	B8									

Table 154: Reading the current position filter (in this example: 35000).

7.2.5. Counter resources

The counter installed in the HIPERFACE DSL® motor feedback system is a 32 bit counter for user purposes that can be incremented as required. The counter can be read, incremented and reset.

7.2.5.1. Read counter

This resource indicates the value of a user-defined counter. The counter value is given as a 32 bit unsigned value.

Direct read access to read counter returns the defining values:

Defining value	Offset	Value
RID		120h
Resource name	0	"READCNT"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	05h – 32 bit, unsigned

Table 155: Read counter defining values.

The counter value is given in the following format:

Byte	Value	Description
3/2/1/0	0000 0000 to FFFF FFFFh	Value of the user-defined counter

Table 156: Read counter definition.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									59	20	00	00	01
Wait for FREL = 1													
Read	Counter (32 bit)												

Table 157: Reading the counter.

7.2.5.2. Increment counter

This resource increments the user-defined 32 bit counter. If the incrementation causes an overrun of the counter, error message 35 appears (see section 6.7.4) and the value of the counter remains at the maximum value.

Direct read access to increment counter returns the defining values:

Defining value	Offset	Value
RID		121h
Resource name	0	"INCCOUNT"
Data size	1	0
Read access level	2	15
Write access level	3	0
Time overrun	4	90
Data type	5	01h - empty

Table 158: Increment counter defining values.

The incrementation is carried out using a write command to this resource that contains no data (length of the long message = 0).

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									11	21	00	00	01
Wait for FREL = 1													

Table 159: Command to increment the counter.

7.2.5.3. Reset counter

This resource carries out a reset of the user-defined 32 bit counter.

Direct read access to reset counter returns the defining values:

Defining value	Offset	Value
RID		122h
Resource name	0	"RESETCNT"
Data size	1	0
Read access level	2	15
Write access level	3	1
Time overrun	4	105
Data type	5	01h - empty

Table 160: Reset counter defining values.

The reset is carried out using a write command to this resource that contains no data (length of the long message = 0).

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									11	22	00	00	01
Wait for FREL = 1													
Read	00	00											

Table 161: Command to reset the counter.

7.2.6. Data storage resources

The user has access to user-defined files to be stored for miscellaneous purposes via the DSL motor feedback system data storage resources.

User data is stored in the non-volatile memory (EEPROM) and protected automatically by CRC checksums. The CRC mechanism provides the user with a very high level of reliability for error detection in relation to the storage of user data.

The following figure contains workflows for handling data storage. Each step represents an individual resource access (long message).

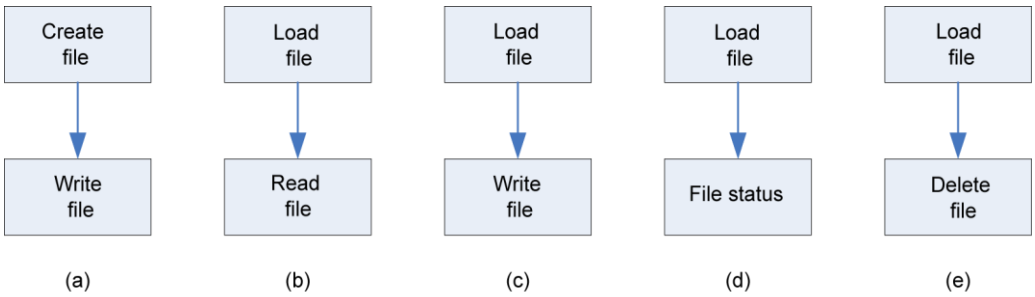


Figure 39: Workflows for data storage: (a) Writing to a new file, (b) Reading from a file, (c) Writing to an existing file, (d) Polling the status of an existing file, (e) Deleting a file

7.2.6.1. Load file

To be able to access an existing file, it must first be loaded using this resource.

Direct read access to load file returns the defining values:

Defining value	Offset	Value
RID		130h
Resource name	0	"LOADFILE"
Data size	1	8
Read access level	2	15
Write access level	3	1
Time overrun	4	130
Data type	5	0Bh - string

Table 162: Load file defined values.

It should be noted that only one file can be loaded at a time. When loading a new file, any hitherto loaded file is discarded.

A file remains loaded until another file is loaded or the DSL motor feedback system is reset or shut down.

A file is specified with its file name that is transmitted to the long message data buffer. If the file name is unknown, the "directory" resource (see section 7.2.6.5) can be used to search for existing files.

The file name can be up to 8 bytes long. Each byte represents one ASCII character. The end of the file name (when less than 8 bytes) is indicated by the character "\0" (00h). It should be noted that upper or lower case characters are valid.

A file can only be loaded if the currently set access level (see section 7.2.4.3) permits the reading of writing of a file. Access rights are determined when a file is created or changed (see section 7.2.6.4).

Byte	Value	Description
0 to 7	Variable	Name of the file to be loaded

Table 163: Load file definition.

Offset-based access enables it to be determined whether or not a verification of the checksums is carried out by the DSL motor feedback system when a file is loaded.

If an error is detected when the verification is carried out, the motor feedback system responds to the "long message" with an error message (4315h, see section 6.7.5). If the verification is not carried out, it is not certain that subsequent read access to the loaded file will produce valid data.

Offset value	Description
0000h	Checksums are verified
0010h	Checksums are not verified
Other values	Reserved

Table 164: Selection of the offset for load file.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	F	I	L	E	1	00	00	00	1D	30	00	00	01
Wait for FREL = 1													
Read													

Table 165: Example of loading a file (in this example: Loading a file with the name "FILE1").

7.2.6.2. Read/write file

Read and write access to a user file is possible via this resource.

Direct read access to read/write file returns the defining values:

Defining value	Offset	Value
RID		131h
Resource name	0	"RWFILE"
Data size	1	8 (Total size depends on file size)
Read access level	2	0 (User determines actual access level)
Write access level	3	0 (User determines actual access level)
Time overrun	4	140
Data type	5	0Bh - string

Table 166. Read/write file defining values.

Before a file can be read or written to, the file must be loaded (see section 7.2.6.1).

Read or write procedures can be carried out by access to any addresses within the file. If an address given for reading causes the file size to be exceeded, an error message is returned. If an address given for writing causes the file size to be exceeded, the file is automatically enlarged. The largest address allowed for this attachment of data is the size of the file.

If the remaining EEPROM memory space is insufficient to accept the enlarged file, access is stopped and an error message is returned (4314h, see section 6.7.5).

By setting the length value for a long message, 2, 4 or 8 bytes can be read, or written in a long message.

The data from a read access or the data for a write access is stored in the long message buffer.

Byte	Value	Description
7 to 0	Variable	Data from, or for a file

Table 167: Definition of reading and writing a file.

The offset value indicates the target address for the read or write access. It should be noted that the files may be a maximum of 32768 bytes in size.

Offset value	Description
0 to 32767	Address for the read or write access

Table 168: Offset value for reading or writing a file.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	11	22	33	44	55	66	77	88	3D	31	33	00	01
Wait for FREL = 1													
Read													

Table 169: Reading or writing to a file (in this example: write 8 bytes to address 0033h).

7.2.6.3. File status

This resource returns the status of the currently loaded file (see section 7.2.6.1).

Direct read access to file status returns the defining values:

Defining value	Offset	Value
RID		132h
Resource name	0	"FILESTAT"
Data size	1	4
Read access level	2	0
Write access level	3	15
Time overrun	4	70
Data type	5	14h – structure with 4 bytes

Table 170: File status defining values.

A write access to "file status" returns the file access rights and the size of the file.

The file status is given in the following format:

Byte	Value	Description
3/2	0000 to FFFFh	File size in bytes
1		Reserved for later use
0, bits 7 to 4		Write access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No write operation permitted
0, bits 3 to 0		Read access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No read operation permitted

Table 171: Definition of reading and writing a file.

For this resource, access to the offset basis is not meaningful as the resource data can be read using a "long message" transaction.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									59	32	00	00	01
Wait for FREL = 1													
Read	20	00	File size 35h 00h										

Table 172: File status (in this example: File with read access 0, write access 2, file size 53 bytes).

7.2.6.4. Create/delete/change file

This resource is used for the creation, changing or deletion of a user file.

Direct read access to create/delete/change file returns the defining values:

Defining value	Offset	Value
RID		133h
Resource name	0	"MAKEFILE"
Data size	1	8
Read access level	2	15
Write access level	3	0 (User determines actual access level)
Time overrun	4	130
Data type	5	0Bh - string

Table 173: Create/delete/change file defining values.

A user file must have been previously created before it can be loaded, written to or read from (see section 7.2.6.1).

Before a file can be changed or deleted, the file must be loaded (see section 7.2.6.1).

To **create a file**, the name must be set in the long message buffer. Unallocated characters of the file name are set to "00h". If there is a user file with the name given already present, the procedure to create the file is canceled with an error message. The name may only consist of printable ASCII characters (20h - 7Eh). The name must be at least one character long.

Byte	Value	Description
7 to 0	Variable	Name of the file to be created

Table 174: Create file definition.

The offset value is also used to create a file.

Bits	Value	Definition
14 – 10		Reserved for later use
9 – 8	11b	Create file
7 – 4		Write access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No write operation permitted
3 – 0		Read access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No read operation permitted

Table 175: Offset value for creating a file.

To **change a file**, only the offset value is used.

Bits	Value	Definition
14 – 10		Reserved for later use
9 – 8	01b	Change file
7 – 4		Write access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No write operation permitted
3 – 0		Read access rights
	0	Public
	1	Operator
	2	Maintenance
	3	Authorized client
	4	Service
	5 – 14	Reserved for later use
	15	No read operation permitted

Table 176: Offset value for changing a file.

To **delete a file**, the file name (of the currently loaded file) must be set in the long message buffer.

Byte	Value	Description
7 to 0	Variable	Name of the file to be deleted

Table 177: Delete file definition.

The offset value is also used to delete a file.

Bits	Value	Definition
14 – 10		Reserved for later use
9 – 8	00b	Delete file
7 – 0		Reserved for later use

Table 178: Offset value for deleting a file.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	F	I	L	E	1	00	00	00	3D	33	10	03	01
Wait for FREL = 1													

Table 179: Creating a file (in the example: Creation of a file with the name "FILE1", read access 0, write access 1).

7.2.6.5. Directory

When this resource is accessed, a list of the existing user files is returned.

Direct read access to directory returns the defining values:

Defining value	Offset	Value
RID		134h
Resource name	0	"DIR"
Data size	1	8
Read access level	2	0
Write access level	3	15
Time overrun	4	130
Data type	5	18h – structure with 8 bytes

Table 180: Directory defining values.

In "directory", only those files are listed that are accessible at the access level set (read or write access).

In addition, by accessing "directory", the current size of the filled and empty user stores can be read.

It should be noted that due to the file header, the user files normally fill more physical stores than their pure data content.

The type of data required by the user is set in the offset value during read access to this resource.

Bits	Value	Definition
14 – 8		Reserved for later use
7 – 0	00h 01h 02h … FFh	Return number of files as well as filled and empty user stores Return name of first user file Return name of second user file … Return name of 255th user file

Table 181: Offset value for "directory".

The "directory" basic data (offset = 00h) is returned in the long message buffer as follows:

Byte	Value	Description
7/6		Reserved for later use
5/4	0 – 65535	Number of filled bytes in the user store
3/2	0 – 65535	Number of empty bytes in the user store
1		Reserved for later use
0	0 – 255	Number of user files

Table 182: Definition of "directory" ("directory" basic data).

The data from the user files (offset > 00h) is returned in the long message buffer as follows:

Byte	Value	Description
7 – 0	Variable	File name

Table 183: Definition of "directory" (data from user files).

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write									7D	34	00	00	01
Wait for FREL = 1													
Read	# file 02h	00	Empty store 1E40h		Used store 0123h		00	00					

Table 184: "Directory" (in this example: Read directory basic data - 2 user files, 123h bytes filled, 1E40h bytes empty).

7.2.7. SensorHub resources

SensorHub resources refer to additional external sensors that are connected to the motor feedback system.

The actual connectivity for external sensors depends on the individual product variant and is specified in the product data sheet.

Connectivity for external sensors is divided into two categories:

- Simple I/Os (inputs, outputs) are connected directly to a suitable DSL motor feedback system. Included in this category, for example, are temperature sensors, temperature switches or digital I/Os. Motor feedback systems with simple I/O connections are generally standard products.
- Enhanced sensors are connected to an external SensorHub component, which itself has a defined interface to the DSL motor feedback system. This architecture is used if several external sensors, or sensors with complex interfaces, are to be connected (e.g. torque or acceleration sensors). SensorHub components are normally customer-specific and are developed in collaboration with SICK.

The following figures give block diagrams for these scenarios:

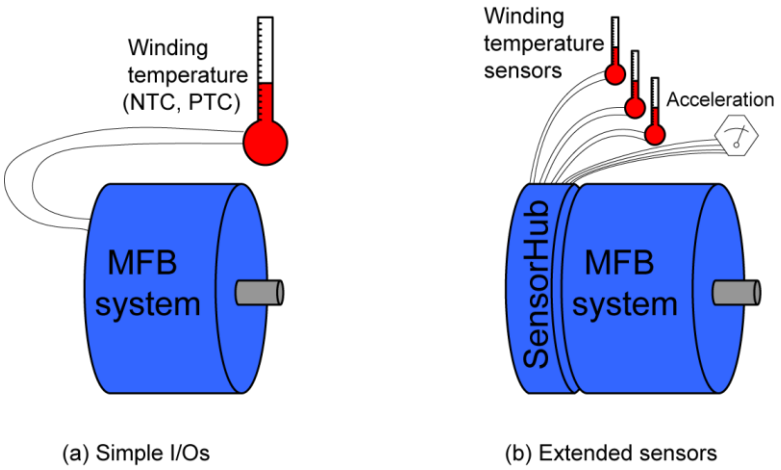


Figure 40: SensorHub categories

7.2.7.1. Access simple I/Os

This resource enables access to simple I/Os connected directly to the motor feedback system.

Direct read access to access simple I/Os returns the defining values:

Defining value	Offset	Value
RID		200h
Resource name	0	"ACCESSIO"
Data size	1	4
Read access level	2	0
Write access level	3	0
Time overrun	4	70
Data type	5	05h – 32 bit, unsigned

Table 185: Access simple I/Os defining values.

The availability of read or write access depends on the product variant. Access to an input or output in a non-specific direction produces an error message (see section 6.7.4, error 41).

In general, simple I/Os can carry out one of the following functions:

Direction	Signal type	Example
Input	Digital	Switch
Output	Digital	Braking control
Input	Analog	Temperature sensor

Table 186: Functions of simple I/Os.

The model name, number and measurement characteristics of simple I/Os for any product variant are specified in the product data sheet. For analog inputs, this also lists the data format and the units of the values measured.

Signals for digital I/Os are specified as follows:

Byte	Value	Description
0	00h 01h 02h to FFh	Set to 0 (output) / Value = 0 (input) Set to 1 (output) / Value = 1 (input) Reserved
1 to 3		Reserved

Table 187: Definition of access simple I/Os.

The offset value gives the I/O number to be accessed. It should be noted that the number of I/Os and the associated I/O numbers are specified in the product data sheet.

Offset value	Description
0 to 127	I/O number

Table 188: Offset value for access simple I/Os.

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	01	00	00	00	00	00	00	00	3A	00	00	00	01
Wait for FREL = 1													

Table 189: "Simple access I/Os" (here: Set digital output with I/O number #0).

7.2.7.2. Manage simple I/Os

This resource enables access to the management functions for simple I/Os connected to the motor feedback system.

Direct read access to manage simple I/Os returns the defining values:

Defining value	Offset	Value
RID		201h
Resource name	0	"MANAGEIO"
Data size	1	4
Read access level	2	0
Write access level	3	2
Time overrun	4	90
Data type	5	05h – 32 bit, unsigned

Table 190: Manage simple I/Os defining values.

The availability of this function depends on the product variant and is specified in the product data sheet.

The offset value determines the requested management function. It should be noted that any additional management functions are specified in the product data sheet.

Offset value	Description
0	Input filter I/O 0
1	Input filter I/O 1
2 to 32767	Reserved

Table 191: Offset value for manage simple I/Os.

The input filter function enables the user to set the low pass characteristic of an analog input. The value of 1 to 100 specifies as a percentage (%) the weighting of new measured values to previously averaged measurements. Examples:

- 100 indicates that there was no filtering.
- 50 indicates that each new measurement will be calculated with a weighting of 50:50 against previous measurements.
- 1 indicates that each new measurement will be calculated with a weighting of 1% against previous measurements.

The values for the input filter functions are determined as follows:

Byte	Value	Description
0	0 1 to 100 101 to 255	Reserved Filter characteristics of the analog input Reserved
1 to 3		Reserved

Table 192: Definition of manage simple I/Os (input filter).

Transaction	Register												
	PC_BUFFER0	PC_BUFFER1	PC_BUFFER2	PC_BUFFER3	PC_BUFFER4	PC_BUFFER5	PC_BUFFER6	PC_BUFFER7	PC_ADD_H	PC_ADD_L	PC_OFF_H	PC_OFF_L	PC_CTRL
Write	32	00	00	00	00	00	00	00	3A	01	00	00	01
Wait for FREL = 1													

Table 193: "Manage simple I/Os" (here: Set filter value 50 for analog input with I/O number #0).

Keywords index

A

Absolute value · 10, 59, 72, 75

B

Bit pattern · 74

C

Cable length · 5
Control signals · 25, 29
CRC · 37, 41, 47, 60, 71, 72, 73, 76, 152, 166, 167

D

DSL Master IP Core · 7, 10, 16, 18, 19, 22, 25, 26, 27, 29, 31, 40, 54, 60, 71, 76, 81, 87, 88

E

Encoder cable · 13, 14, 23
Encoder ID · 55
Encoder status · 77, 78, 79
Encoder temperature · 124, 146
Error handling · 29, 73, 95, 97, 99, 102
External sensors · 6, 12

F

Free running mode · 7, 82, 84, 85
Frequency inverter cycle · 7, 8, 9, 10, 11, 12, 27
Frequency inverter PSDI · 7
Full-duplex SPI interface · 6

I

Implementation of the IP Core · 22
Interface blocks · 16, 22
interrupt · 29, 49

L

Long message · 11, 21, 38, 47, 51, 61, 90, 92, 107, 116, 125, 127, 129, 143, 148

O

Online Status · 36, 38, 39, 40, 43, 44, 45, 72, 86, 100, 167

P

Parallel bus · 25, 36
Parameter data · 92, 166
Parameters Channel · 9
Pin functions · 22
Position data · 7
Process data · 6
Protocol package · 7

Q

Quality monitoring · 37, 40, 41, 43, 44, 45, 47, 50, 82, 83

R

Resolution · 88, 117, 137

S

Safe position · 9, 10, 30, 32, 37, 39, 40, 46, 59, 74, 75, 87, 88
SensorHub channel · 9
SensorHub resources · 161
Set position · 141
Short message · 10, 11, 12, 21, 34, 38, 41, 47, 48, 51, 67, 77, 90, 92, 97
`Speed` · 41, 57, 87
SYNC mode · 7, 21, 82, 85, 86, 87
SYNC signal · 59
Synchronous · 7, 10, 11, 12, 85, 87, 88, 131
System diagnostics · 82, 83

T

Time sequence for SPI PIPE · 28

V

Voltage supply · 15, 168

Glossary

8B/10B	8 bit/10 bit code (line code for transmission of 8 bits with data in 10 bit lengths to achieve DC balance)
CRC	Cyclic Redundancy Check (algorithm to determine data checksum)
DSL	Digital Servo Link, complete name: HIPERFACE DSL®
EDIF	Electronic Design Interchange Format (format for electronic exchange of FPGA netlists)
FIFO	First in – First out (storage method in which the first stored elements are the first to be discarded)
FPGA	Field Programmable Gate Array (programmable digital logic component)
IP Core	Intellectual Property Core, for integration into ICs or chip provided for FPGAs
Long Message	Protocol component for polling parameter data of an encoder that must first be processed by the encoder.
Mail message	Special "short message" for transmission of safety oriented test messages to the encoder
Motor feedback system	Rotary or linear encoder for use in servo drives
RS485	Radio Sector Standard 485 (also designated as EIA-485 or TIA-485-A standard for serial data transmission over symmetric pair cables)
RSSI	Received Signal Strength Indicator
SensorHub	Interface between a motor feedback system and an external sensor component in a drive system
Short Message	Protocol component for polling directly transmitted parameter data of an encoder
SPI	Serial Peripheral Interface (serial bus system for digital switching)
VHDL	Very high speed integrated circuit Hardware Description Language (hardware abstraction language for FPGAs)

Versions

Date	Version	Change
3/9/2010	00	First issue
6/17/2010	UC36	Chap. 3.2.2: IP Core installation removed (now in IP Core manual) Chap. 5.2.1/5.2.2: Correction of Online Status bit description Chap. 5.3./5.3.4/5.3.5: Correction of Event register bit description Chap. 5.3.9: Update of IP Core version number Chap. 5.3.10/5.3.11/5.3.14: Description of "sign" indicator added Chap. 5.4.2: Correction of description of Register Status2
9/9/2010	UL39	General: Change of HIPERFACE DSL basic frequency to 75 MHz, documentation of the associated changes. Chap. 2: Change to time parameters due to new basic frequency Chap. 3.1: Removal of interface wiring with four core cables in the motor cable Chap. 3.2: Change to IP Core characteristics due to new basic frequency Chap. 6.6.4: Removal of unused error message 0x15. Update of error definitions 0x20 to 0x26 Chap. 7.1.3: Update of description of direct resource access Chap. 7.2.1: Update of description of node resources Chap. 7.2.3.12: Update of definition of error protocol Chap. 7.2.3.13: Removal of the definition of usage history for external temperature
1/26/2011	V219	General: Amendment of chapters for various IP Core interface blocks. Renaming of Online DSL Master Status to Online Status. Removal of resources no longer referred to. Chap. 4: Details of various interface blocks and new IP Core signals POS_READY, SYNCD, BIGEND Chap. 5.3.1: New PRDY control bit Chap. 6.6/6.7: Chapter structure revised Chap. 7.2: Amendment of resources data type Chap. 7.2.3.12: Change of definition of current histogram Chap. 7.2.4.1: Description of the use of the reset command to store non-volatile values Chap. 7.2.4.5: Amendment of the "user-defined warnings" resource Chap. 7.2.4.6: Amendment of the "factory settings" resource Chap. 7.2.4.7: Amendment of the "user-defined encoder index" resource Chap. 7.2.6.1: Description of the option to load a file without CRC check Chap. 7.2.7: Amendment of SensorHub resources
11/17/2011	VO52	Chapter concerning interface blocks moved to IP Core manual Amendment of Chapter 4.6 Chap. 5.3: Additional information on address allocation Chap. 5.3.6: Amendment of the effect of the mask on the SUM bit in the event registers. Chap. 5.4.3: Additional information on position value Chap. 7.2.2.6: Amendment of the hardware version Chap. 7.2.3. et seq.: Provision of missing RID values, adaptation of time overruns Chap. 7.2.3.12: Removal of unused acceleration histogram Chap. 7.2.4.1: Amendment of the description of the shut-down command Chap. 7.2.4.8: Amendment of the description of the position filter Chap. 7.2.6.5: Correction of empty/filled stores

8/24/2012	W740	Designations changed Horizontal channel → Process data channel Vertical channel → Safe channel Incremental position → Fast position Absolute position → Safe position Vertical position → Safe position Chap. 3.: Amendment of Table 4 Chap. 3.1.1: Removal of FPGA block in Figure 5 and Table 4 Chap. 3.1.2: Removal of FPGA block in Figure 6 and Table 5 Chap. 3.1.3: Amendment of "motor feedback voltage supply" Chap. 3.3.2: Amendment of Table 11 Chap. 4.4.3: Amendment of description of the LINK signal Chap. 5.3.3: Amendment of description of bit 0 Chap. 6.2.2: Amendment of Table 32 with link status Chap. 7.2.2.1 to 7.2.7.2: Change to description of write and read commands Chap. 7.2.6.4: Amendment to restriction of file names Adaptation to IP core revision 1.04 New chapters 4.6.4 – 4.6.6 on new test signals Chap. 5.3.3 Revised quality monitor rules Chap. 5.3.9 Revised version register encoding New chap. 5.3.10 on new register error counter
5/31/2013	XH05	Clarification of IP core reset signal (high active) Adaptation to IP core revision 1.05 Chap. 2.1: Introduction of position estimator Chap. 3.2: Update IP-Core block diagrams, display of all combinations New chapter 4.4.7: Position estimator error signal Chapter 4.6.2: Renaming of pos_not_valid to pos_estimated New chapter 4.6.4: New vpos_error signal Chapter 5.3: Update of register map Chapter 5.3.23: ACC_ERR_CNT register address moved New chapters 5.3.24-25: Position estimator registers

Table 194: Document versions.

8013607_XH05/2013-06-28 · 7MSUP (2010-02) · USmod 4c int40

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